

1 / 44
FIG. 1

1700(2700,3700)



1740(1720)(2740(2720),3740(3720))

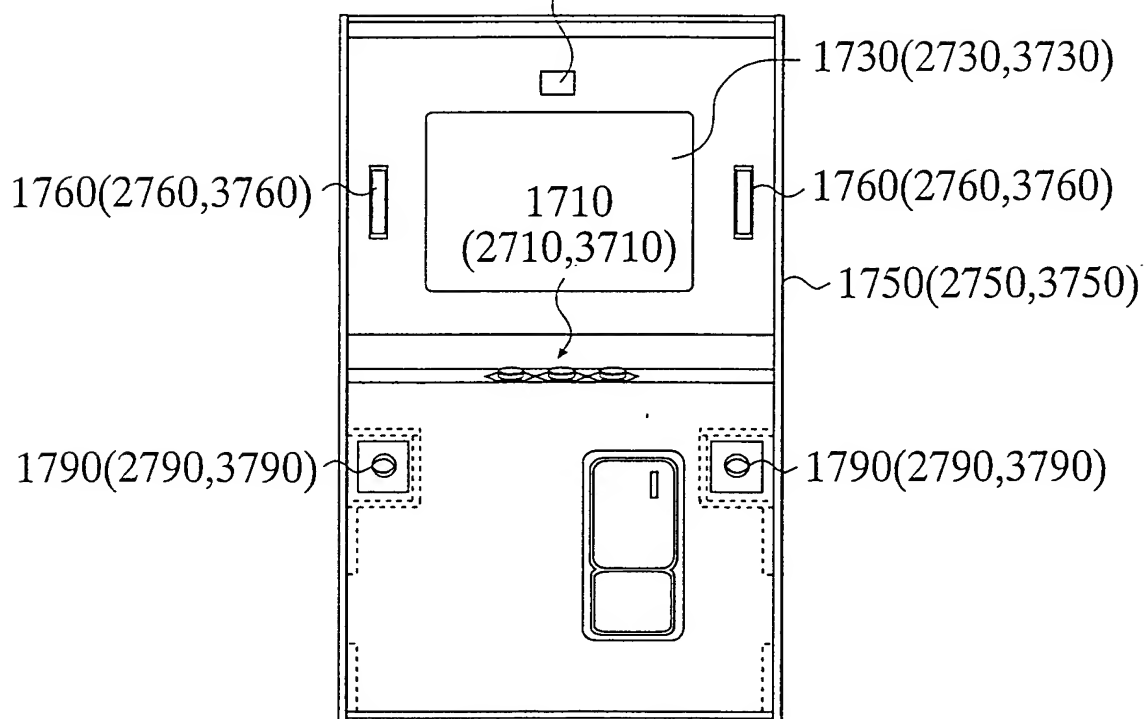
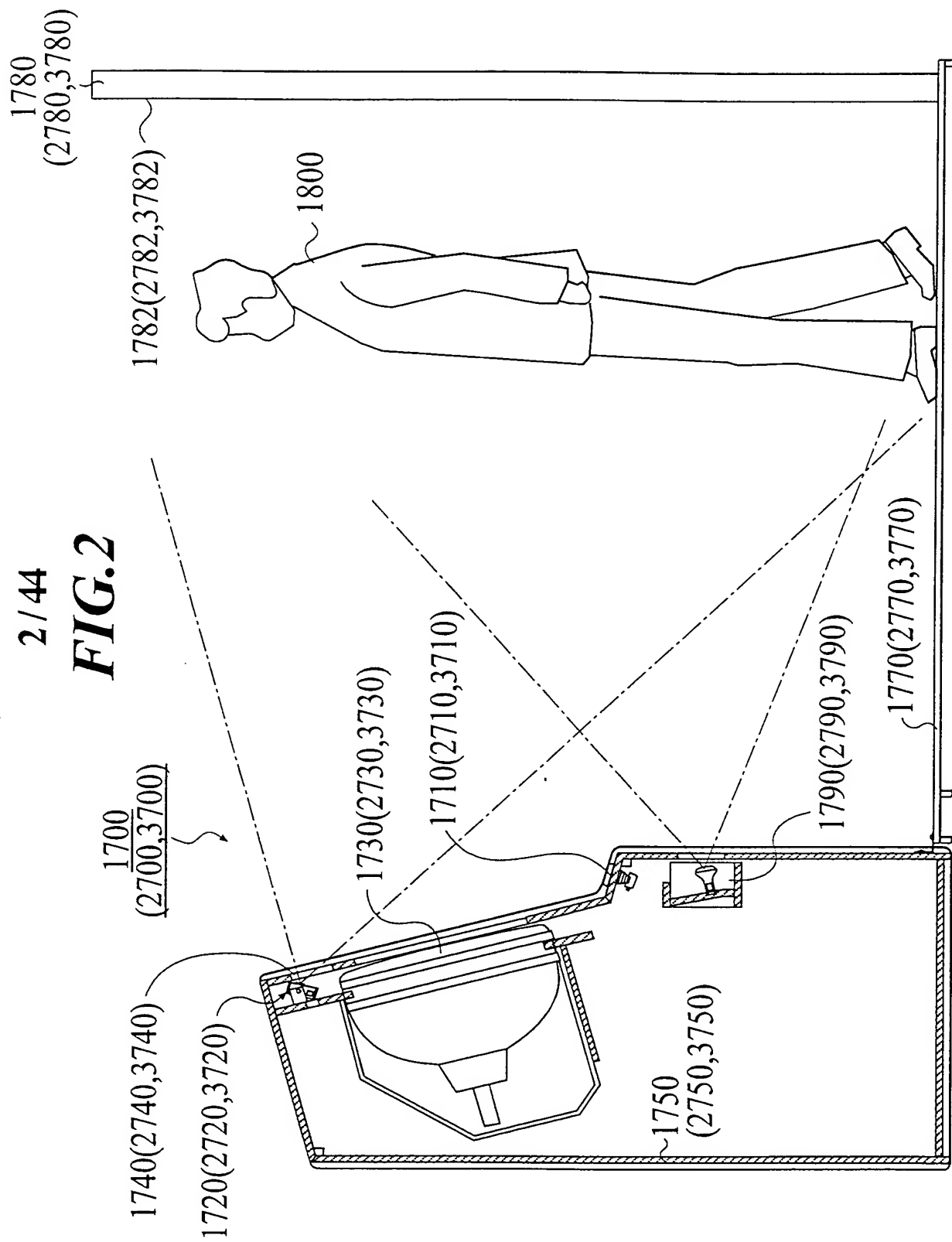


FIG. 2



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FIG.3

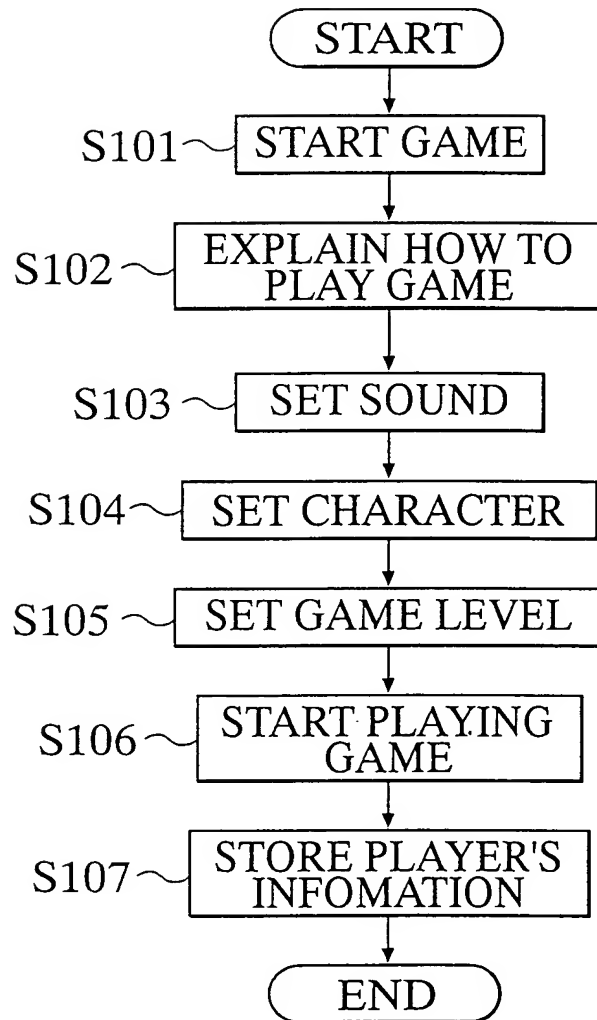


FIG.4

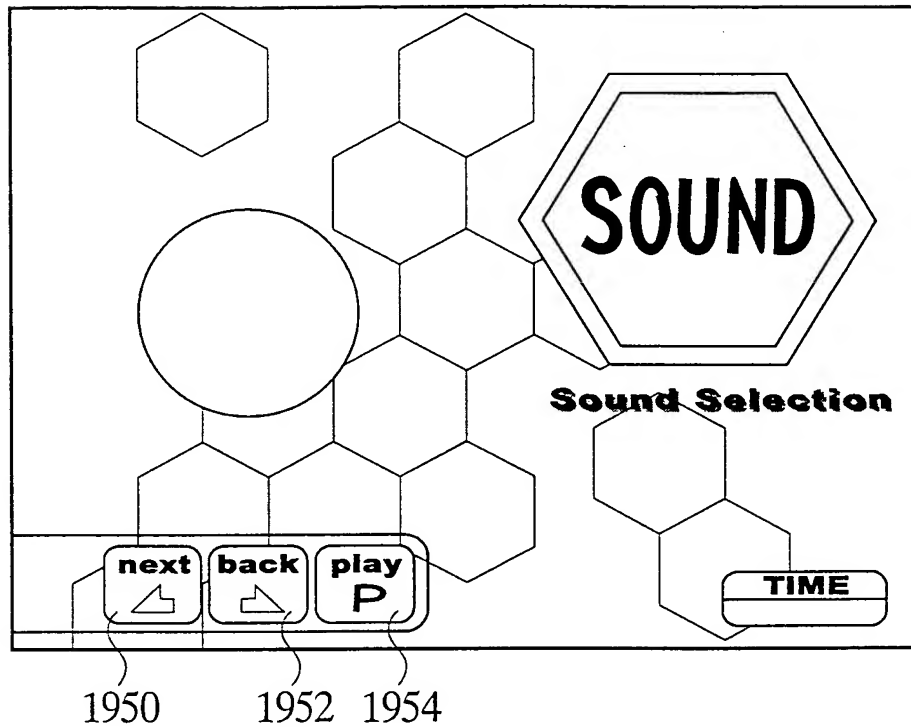
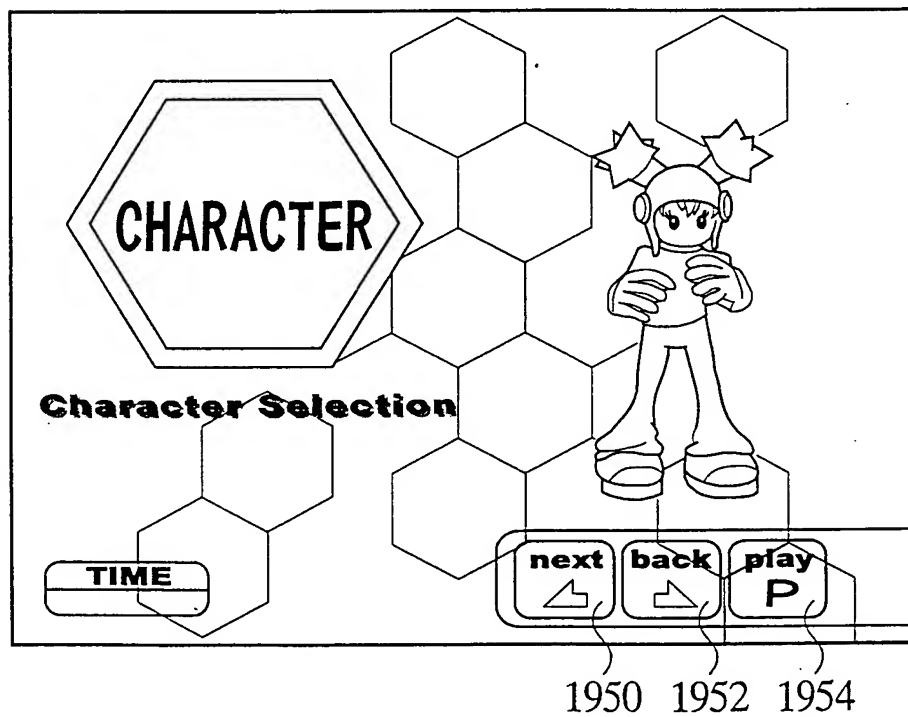


FIG.5



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FIG.6

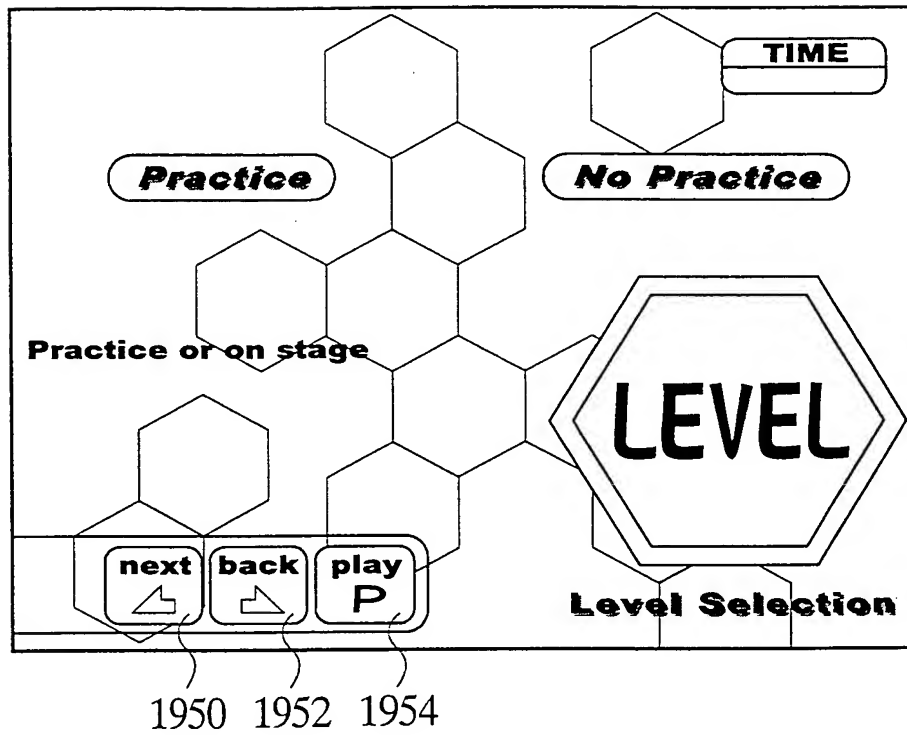


FIG.7

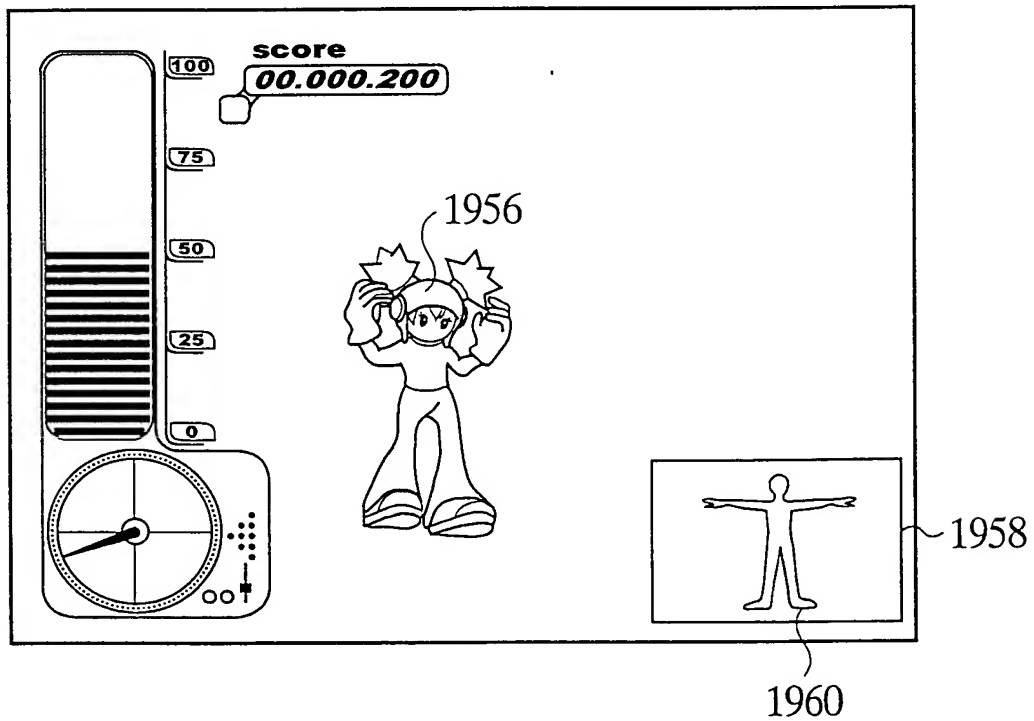


FIG. 8

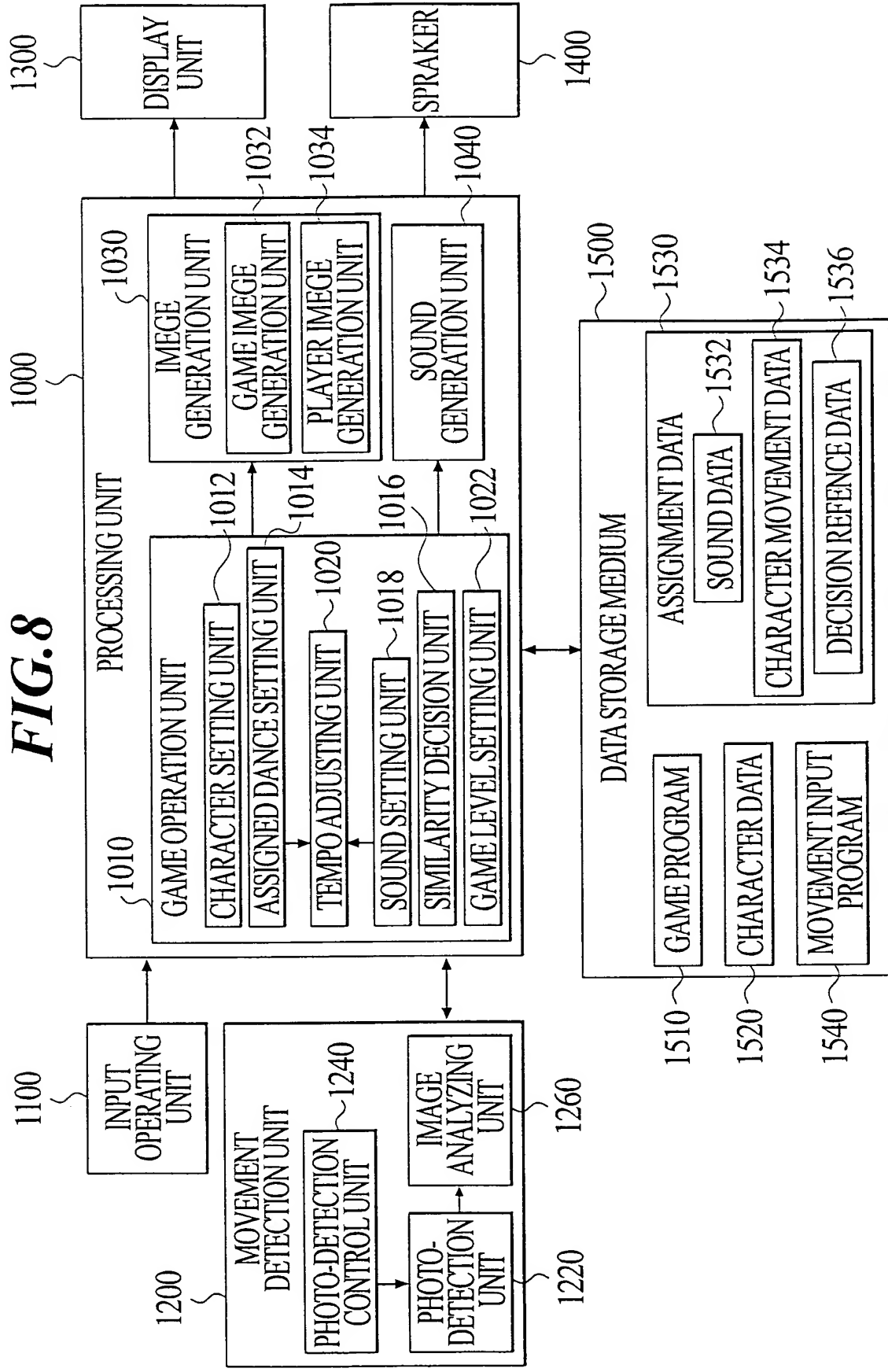
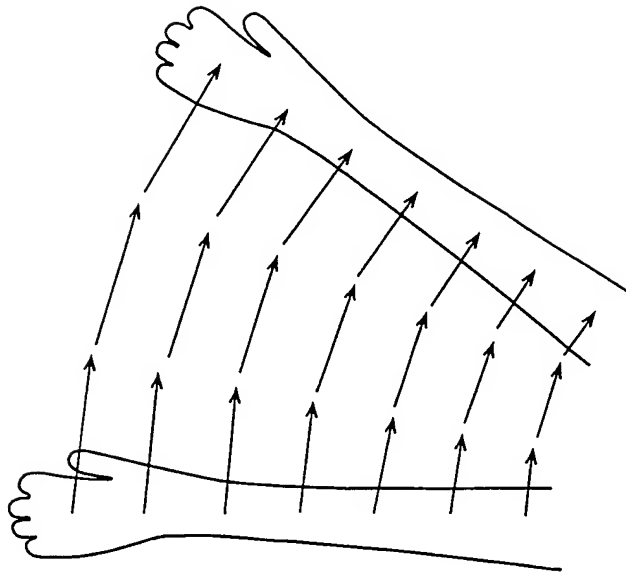


FIG.9**FIG.10**

	DIRECTION	MAGNITUDE	SPEED
PLAYER'S MOVEMENT	$\alpha 1$	$\beta 1$	$\gamma 1$



(DIRECTION α , MAGNITUDE β , SPEED γ)

DECISION REFERENCE DATA				
	t1	t2	t3	...
DANCE 1	PART a	$(\alpha\ 11, \beta\ 11, \gamma\ 11)$	$(\alpha\ 12, \beta\ 12, \gamma\ 12)$	$(\alpha\ 13, \beta\ 13, \gamma\ 13)$
	PART b	$(\alpha\ 21, \beta\ 21, \gamma\ 21)$	$(\alpha\ 22, \beta\ 22, \gamma\ 22)$	$(\alpha\ 23, \beta\ 23, \gamma\ 23)$
	\vdots	\vdots	\vdots	...
DANCE 2	PART a	$(\alpha\ 11', \beta\ 11', \gamma\ 11')$	$(\alpha\ 12', \beta\ 12', \gamma\ 12')$	$(\alpha\ 13', \beta\ 13', \gamma\ 13')$
	PART b	$(\alpha\ 21', \beta\ 21', \gamma\ 21')$	$(\alpha\ 22', \beta\ 22', \gamma\ 22')$	$(\alpha\ 23', \beta\ 23', \gamma\ 23')$
	\vdots	\vdots	\vdots	...

FIG.12

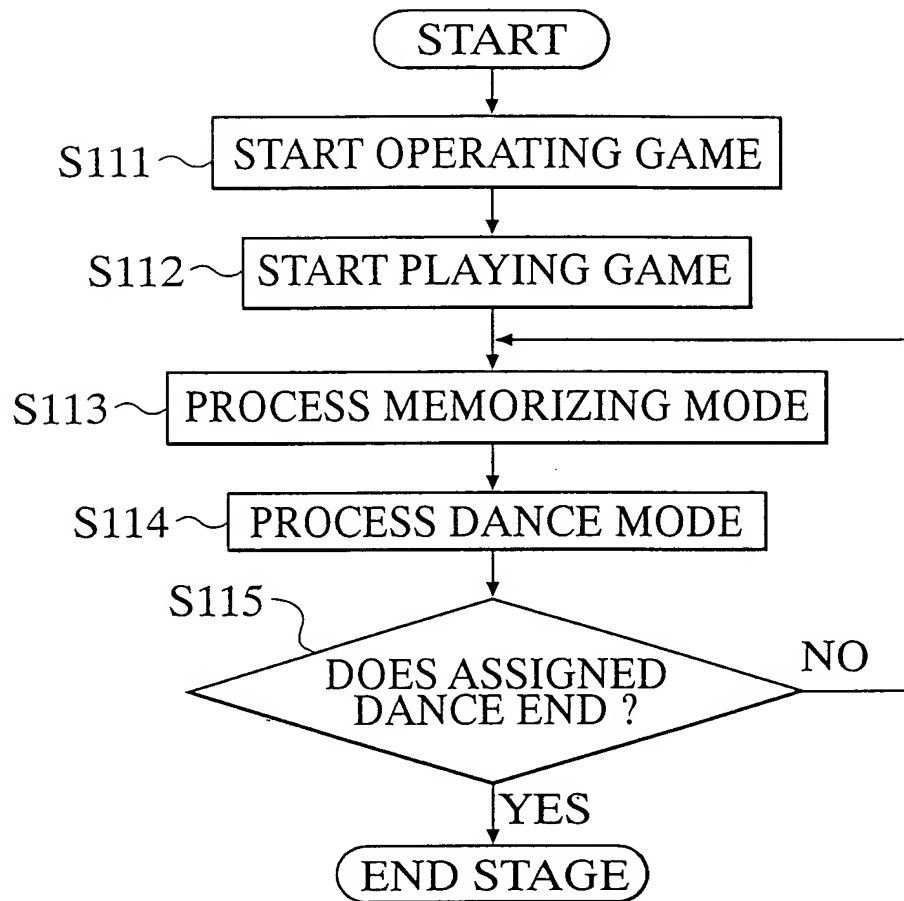
1534



(COORDINATES:X,Y,Z)

DANCE 1	POSITION DATA			
	FRAME 1	FRAME 2	FRAME 3	...
A	PART a	(Xa1, Ya1, Za1)	(Xa2, Ya2, Za2)	(Xa3, Ya3, Za3)
	PART b	(Xb1, Yb1, Zb1)	(Xb2, Yb2, Zb2)	(Xb3, Yb3, Zb3)
	PART c	(Xc1, Yc1, Zc1)	(Xc2, Yc2, Zc2)	(Xc3, Yc3, Zc3)
	⋮	⋮	⋮	...
B	PART a	(Xa1', Ya1', Za1')	(Xa2', Ya2', Za2')	(Xa3', Ya3', Za3')
	PART b	(Xb1', Yb1', Zb1')	(Xb2', Yb2', Zb2')	(Xb3', Yb3', Zb3')
	PART c	(Xc1', Yc1', Zc1')	(Xc2', Yc2', Zc2')	(Xc3', Yc3', Zc3')
	⋮	⋮	⋮	...

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FIG.13



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FIG.14

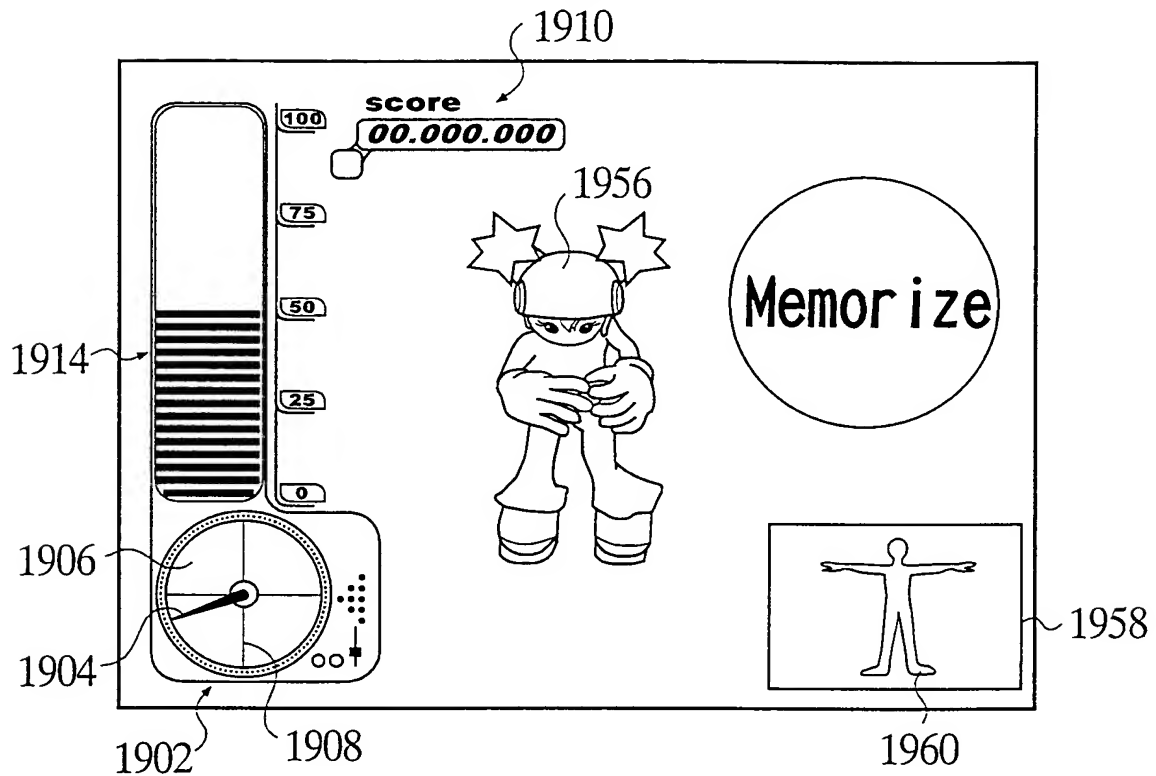
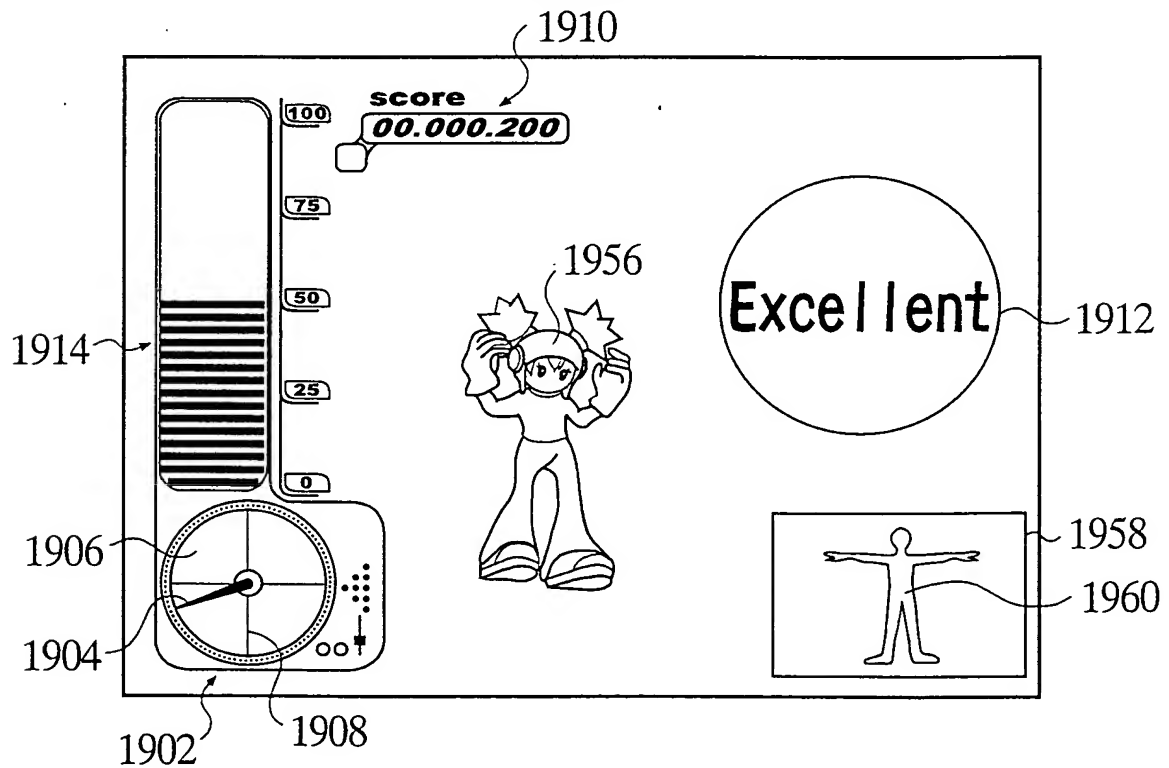


FIG.15



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FIG.16

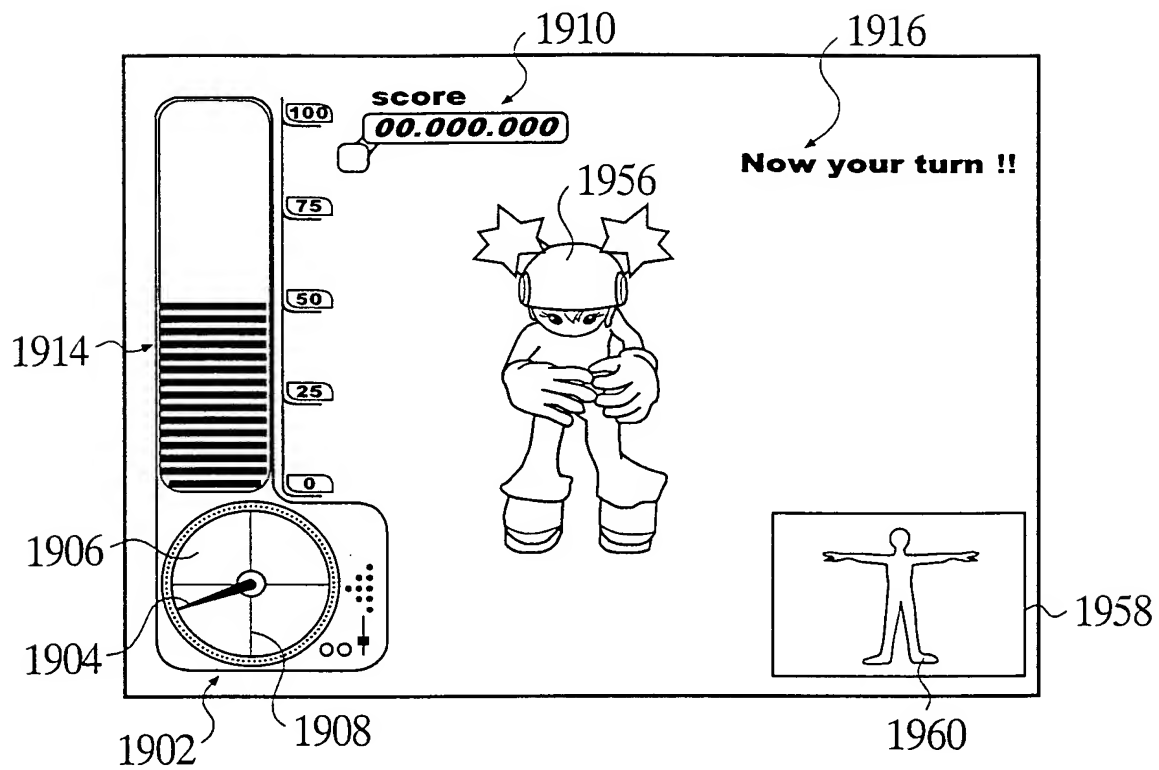


FIG.17

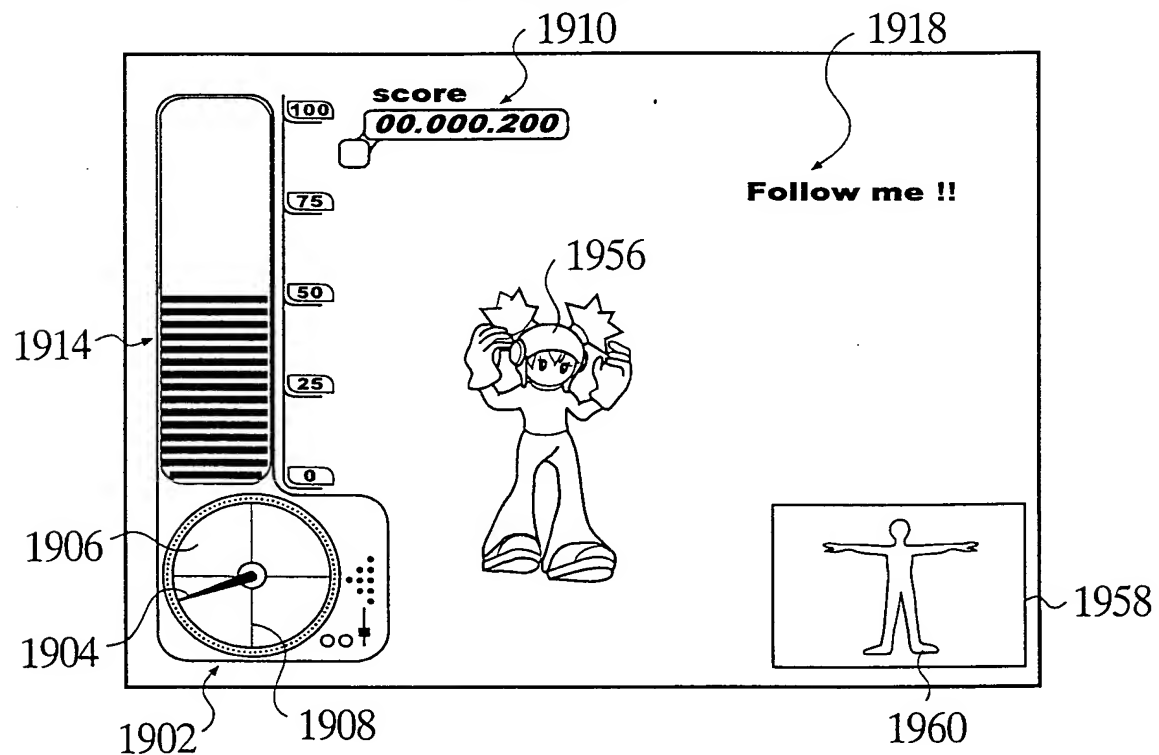
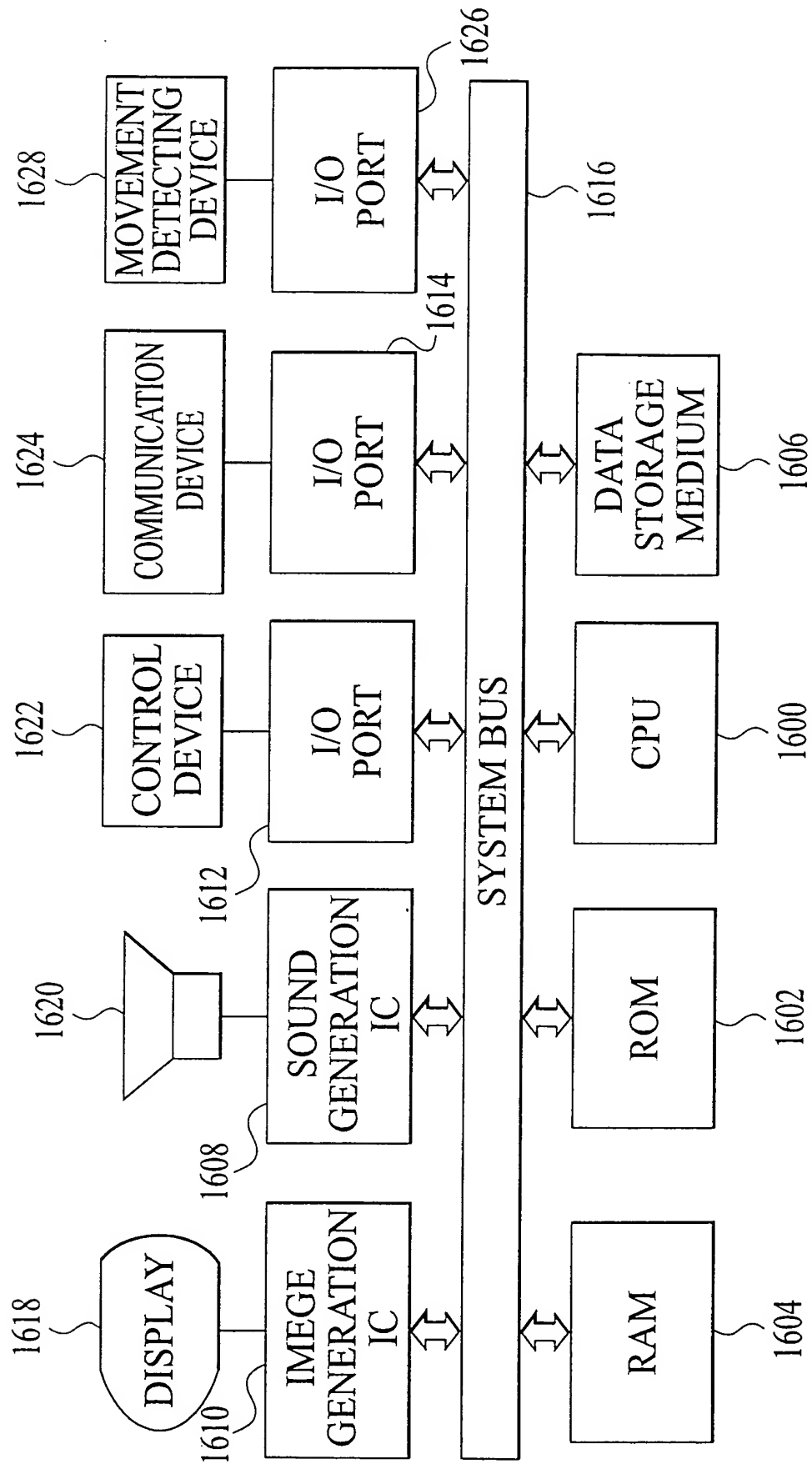


FIG. 18



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FIG.19A

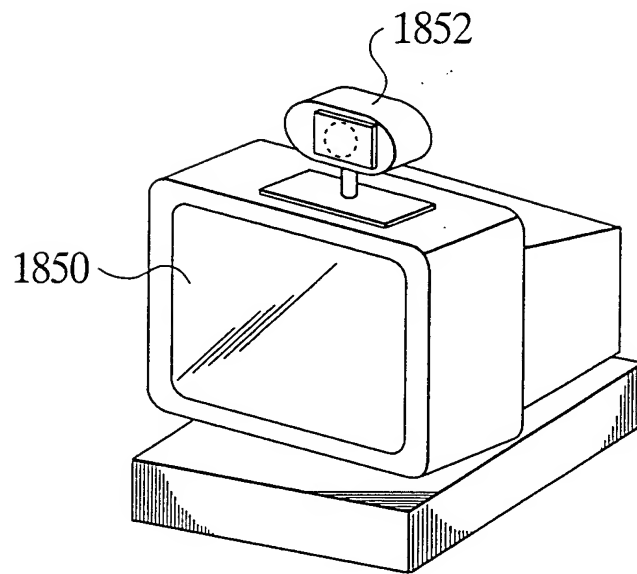
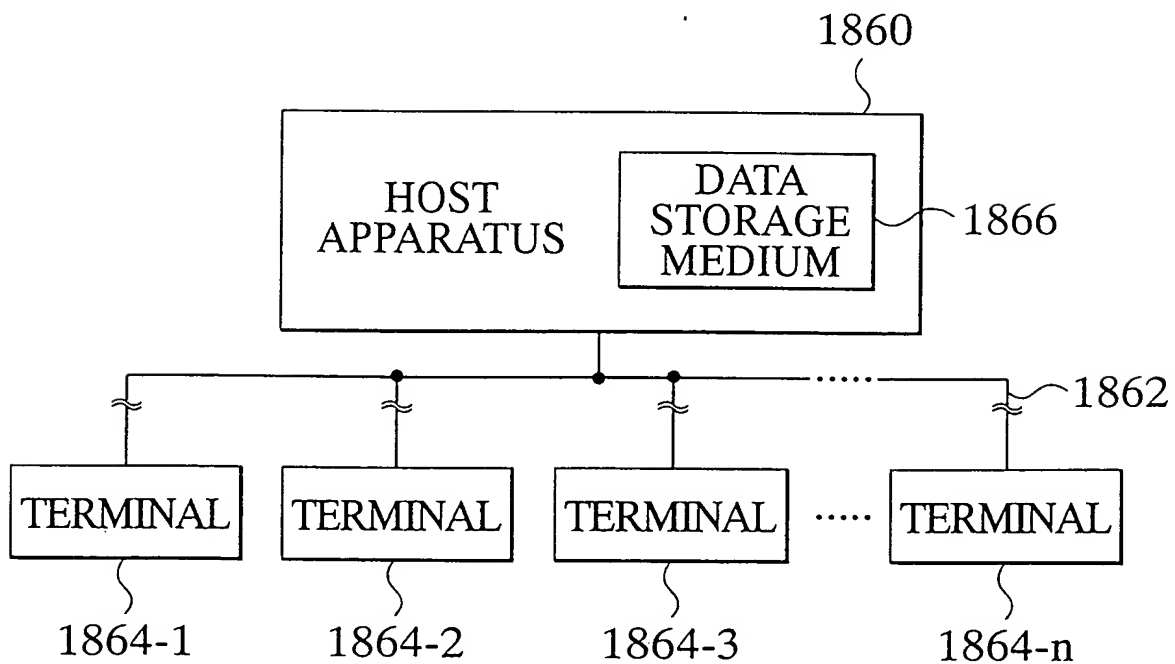


FIG.19B



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FIG.20

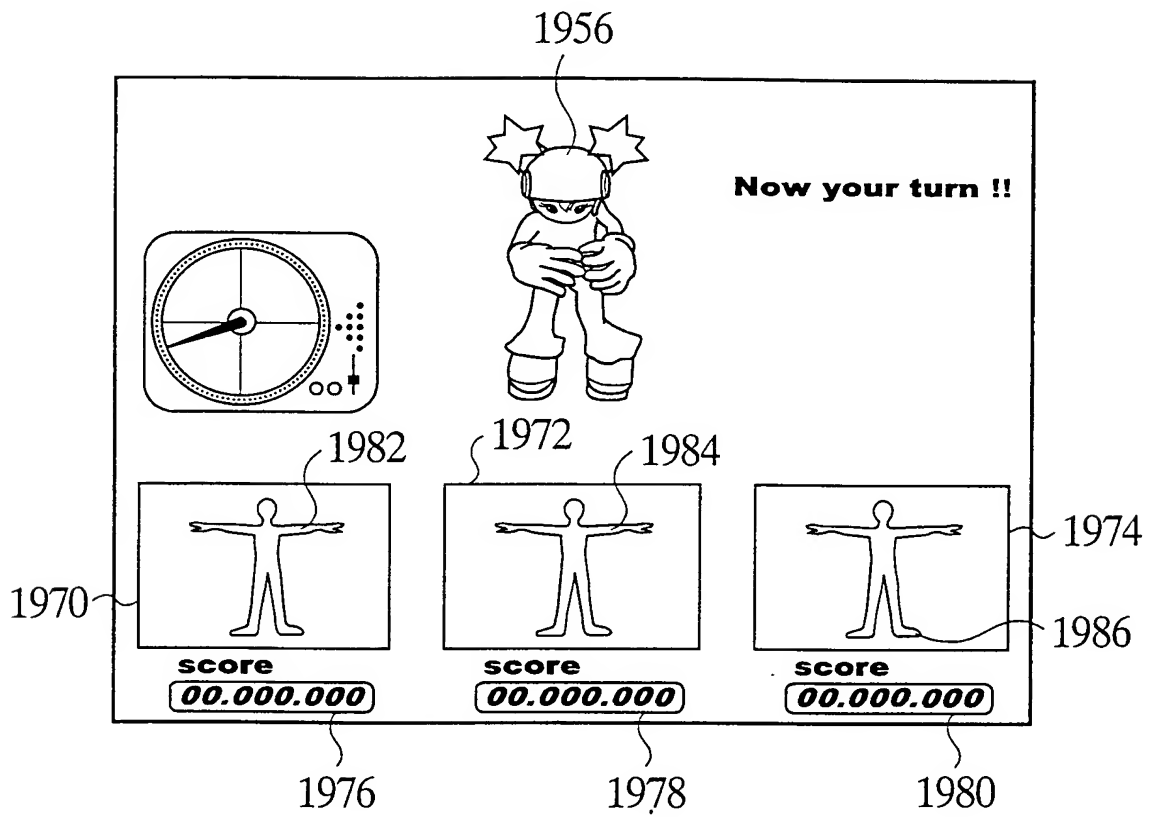
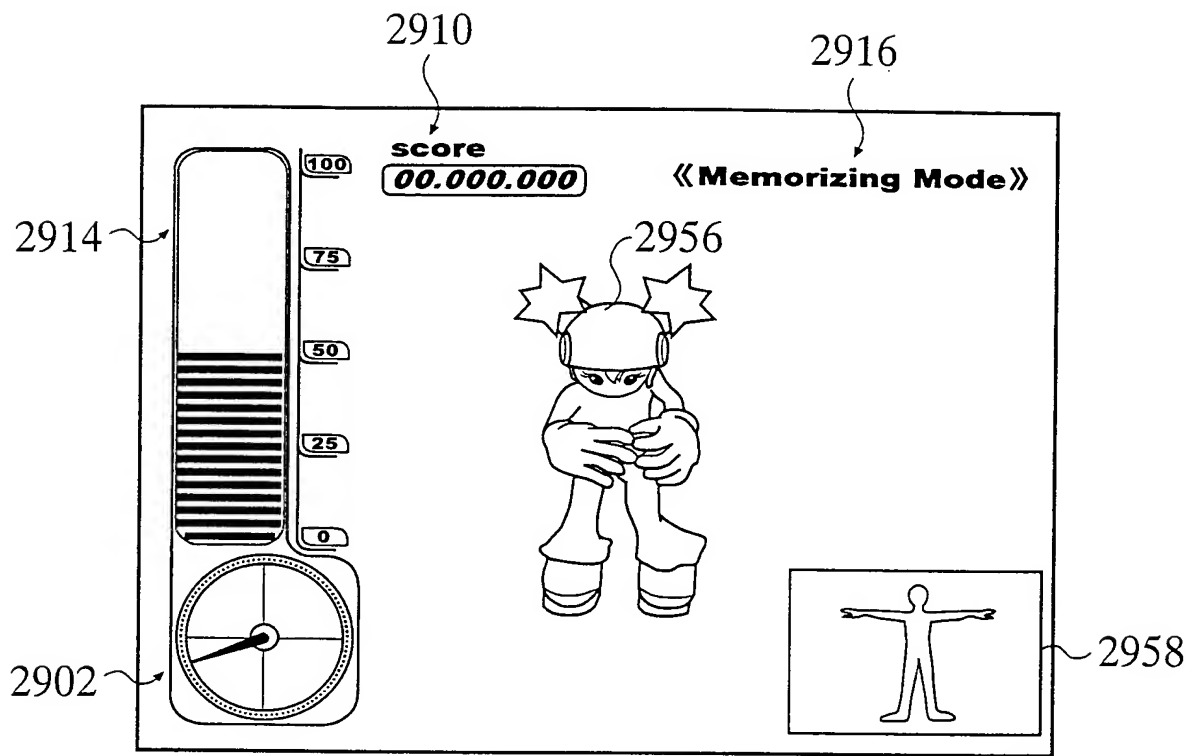


FIG.21



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FIG.22

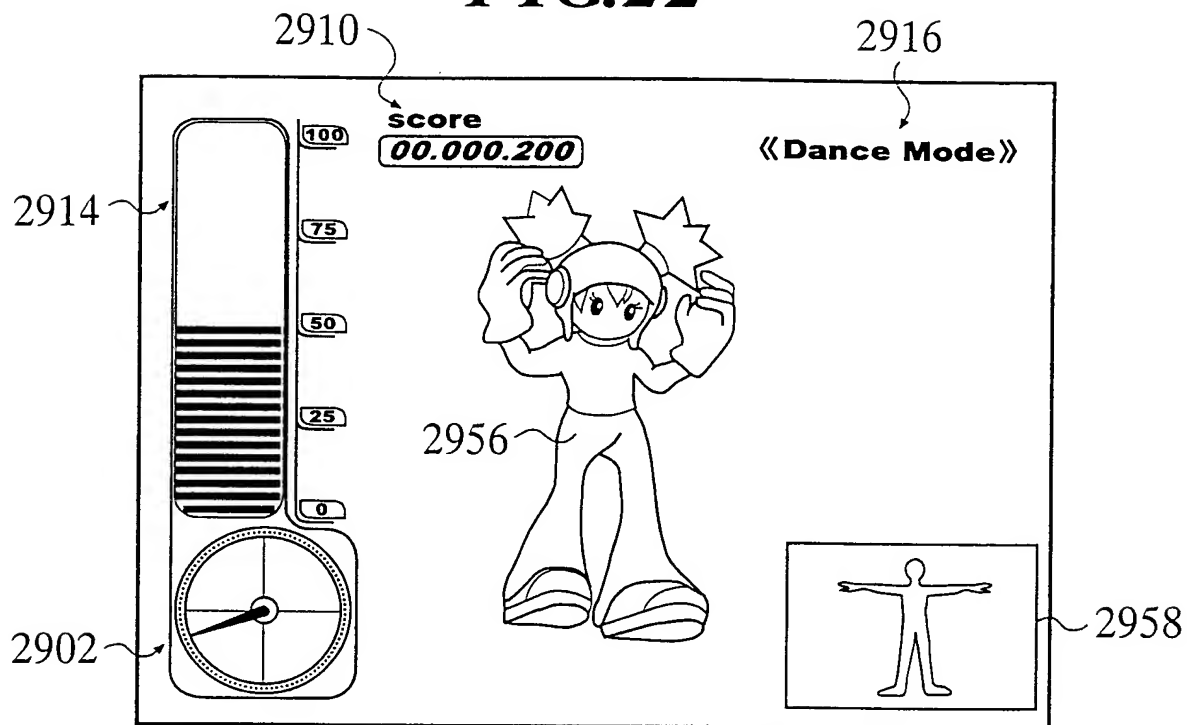


FIG.23

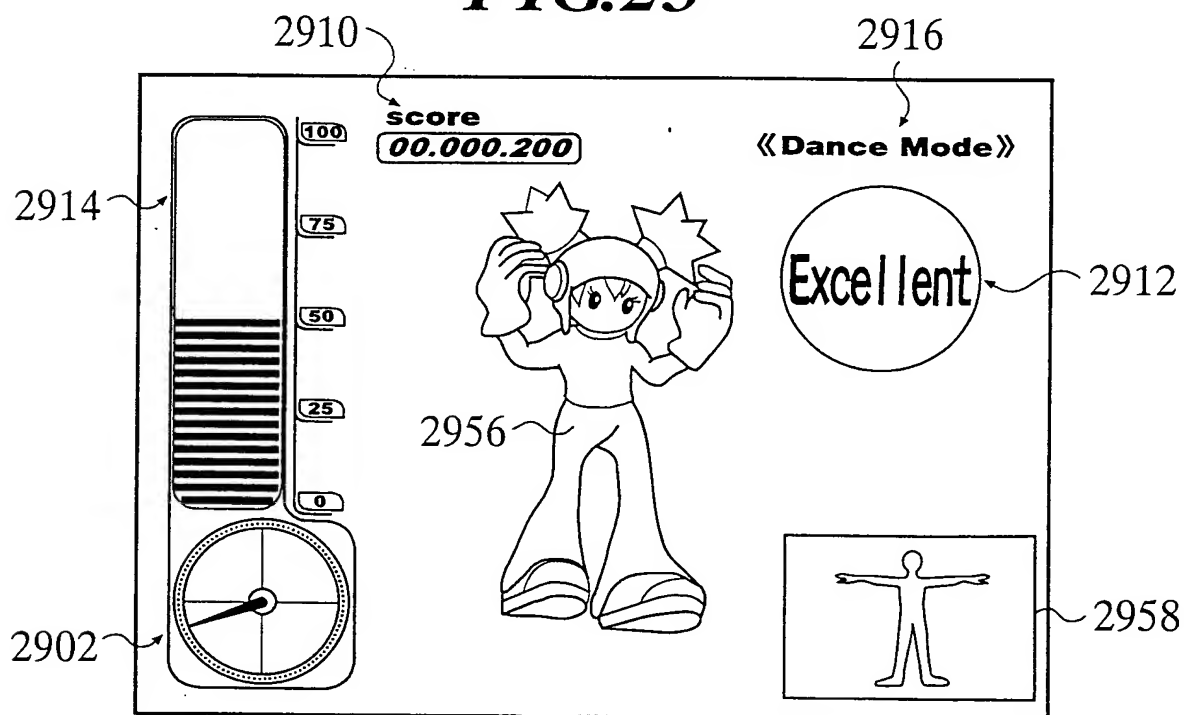
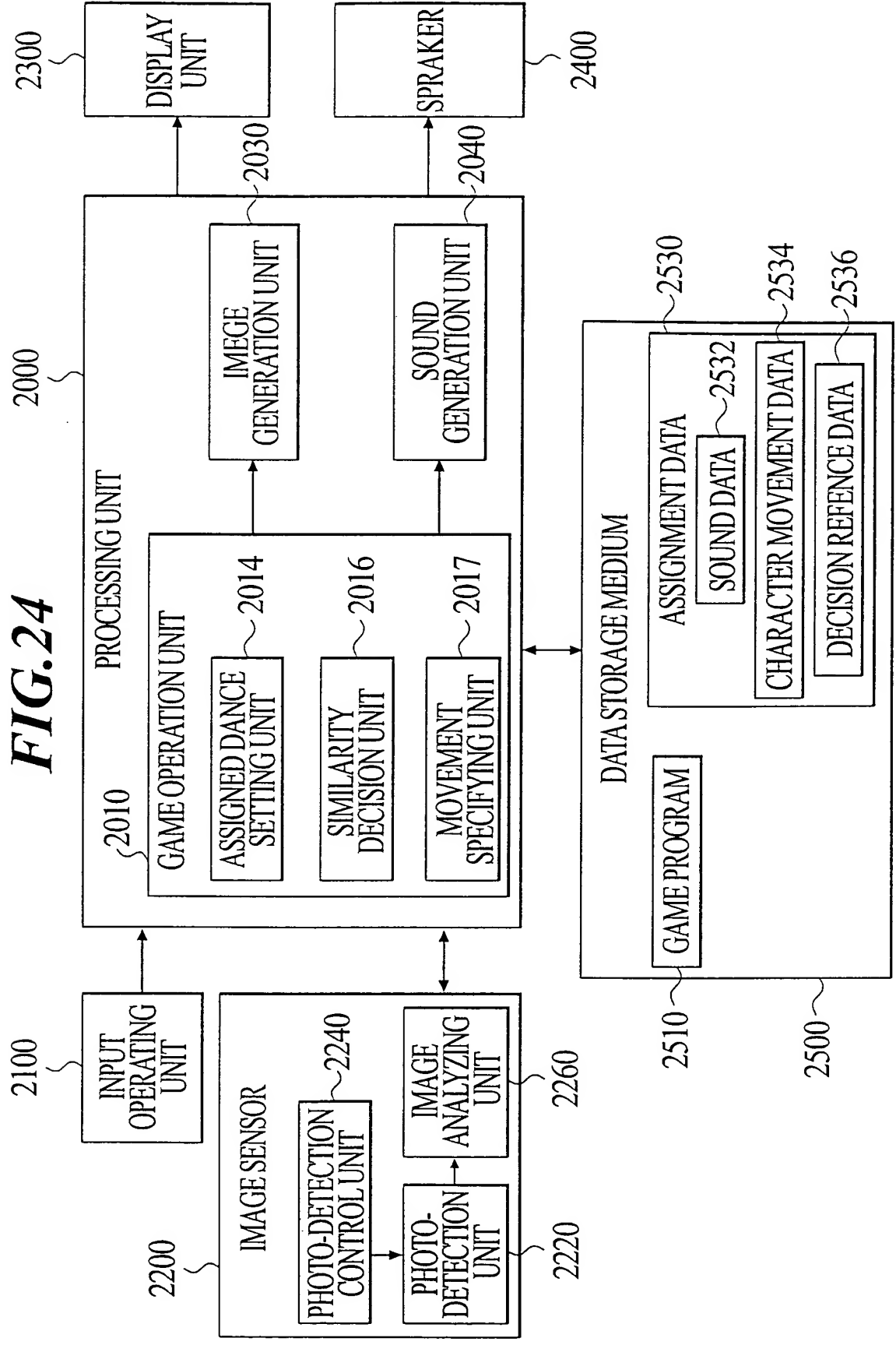


FIG. 24



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(COORDINATES:X,Y,Z)

POSITION DATA				
		FRAME 1	FRAME 2	FRAME 3
DANCE 1	PART a	(Xa1, Ya1, Za1)	(Xa2, Ya2, Za2)	(Xa3, Ya3, Za3)
	PART b	(Xb1, Yb1, Zb1)	(Xb2, Yb2, Zb2)	(Xb3, Yb3, Zb3)
	PART c	(Xc1, Yc1, Zc1)	(Xc2, Yc2, Zc2)	(Xc3, Yc3, Zc3)
	⋮	⋮	⋮	⋮
DANCE 2	PART a	(Xa1', Ya1', Za1')	(Xa2', Ya2', Za2')	(Xa3', Ya3', Za3')
	PART b	(Xb1', Yb1', Zb1')	(Xb2', Yb2', Zb2')	(Xb3', Yb3', Zb3')
	PART c	(Xc1', Yc1', Zc1')	(Xc2', Yc2', Zc2')	(Xc3', Yc3', Zc3')
	⋮	⋮	⋮	⋮



(DIRECTION α , MAGNITUDE β , SPEED γ)

DECISION REFERENCE DATA				
	t1	t2	t3	...
DANCE 1	1ST REGION	(α 11, β 11, γ 11)	(α 12, β 12, γ 12)	(α 13, β 13, γ 13)
	2ND REGION	(α 21, β 21, γ 21)	(α 22, β 22, γ 22)	(α 23, β 23, γ 23)
	3RD REGION	(α 31, β 31, γ 31)	(α 32, β 32, γ 32)	(α 33, β 33, γ 33)
	4TH REGION	(α 41, β 41, γ 41)	(α 42, β 42, γ 42)	(α 43, β 43, γ 43)
DANCE 2	1ST REGION	(α 11', β 11', γ 11')	(α 12', β 12', γ 12')	(α 13', β 13', γ 13')
	2ND REGION	(α 21', β 21', γ 21')	(α 22', β 22', γ 22')	(α 23', β 23', γ 23')
	3RD REGION	(α 31', β 31', γ 31')	(α 32', β 32', γ 32')	(α 33', β 33', γ 33')
	4TH REGION	(α 41', β 41', γ 41')	(α 42', β 42', γ 42')	(α 43', β 43', γ 43')

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FIG.27

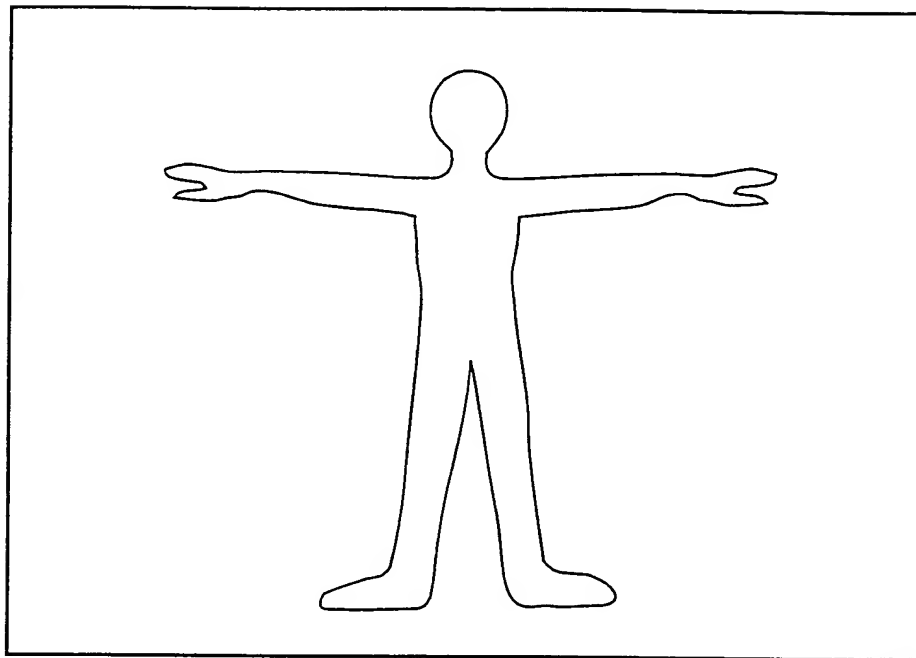
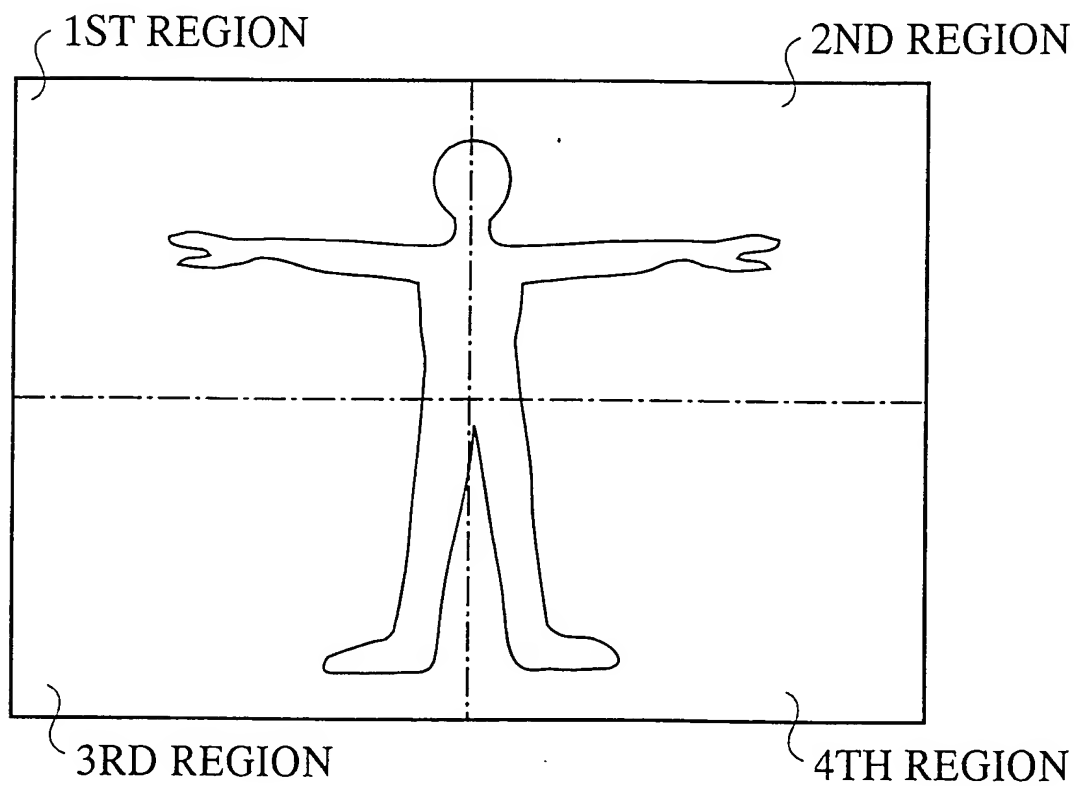


FIG.28



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FIG.29

	DIRECTION	MAGNITUDE	SPEED
1ST REGION	$\alpha 1$	$\beta 1$	$\gamma 1$
2ND REGION	$\alpha 2$	$\beta 2$	$\gamma 2$
3RD REGION	$\alpha 3$	$\beta 3$	$\gamma 3$
4TH REGION	$\alpha 4$	$\beta 4$	$\gamma 4$

FIG.30A

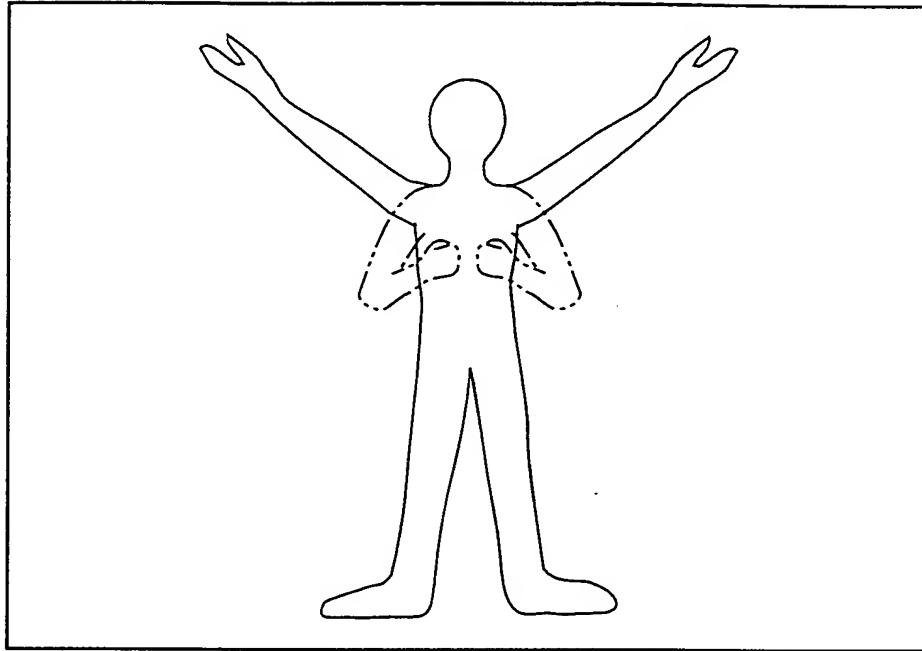


FIG.30B

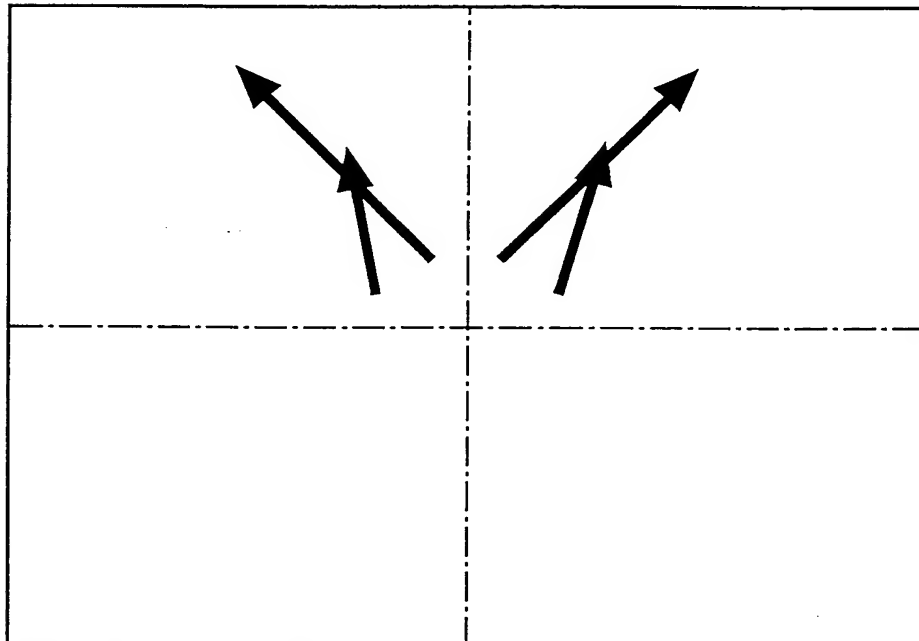


FIG.31A

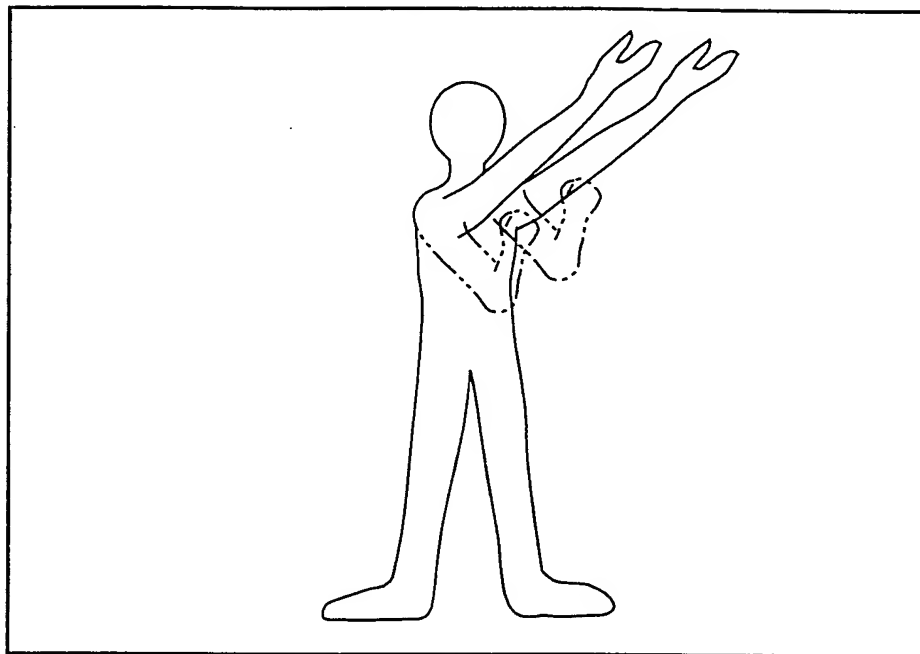
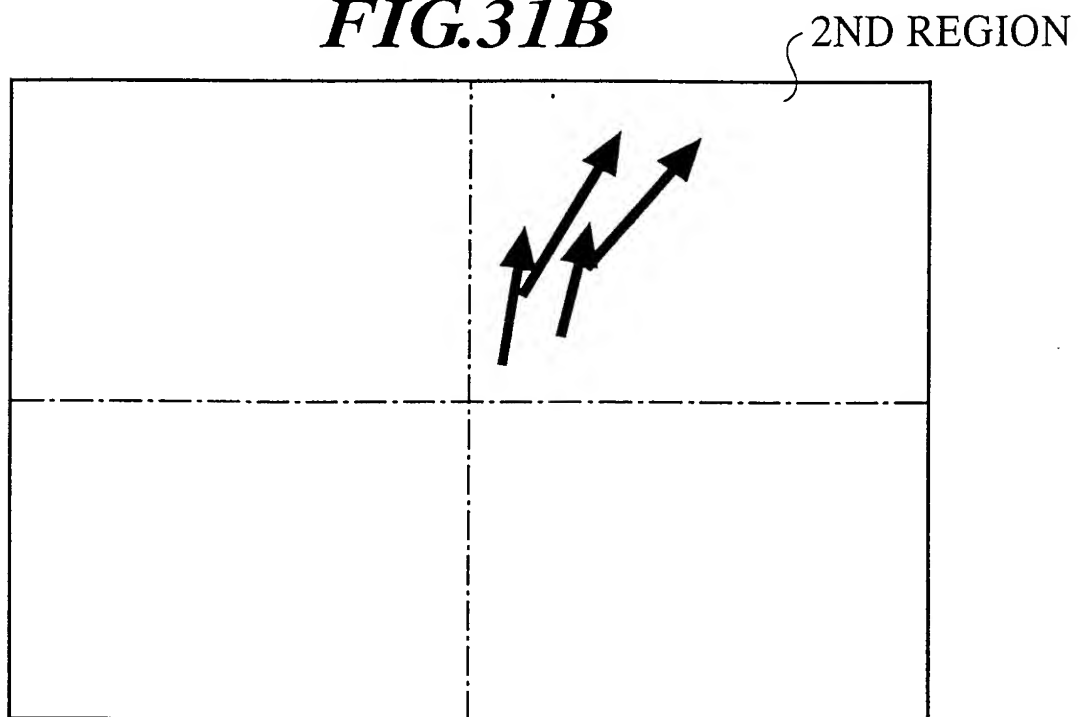
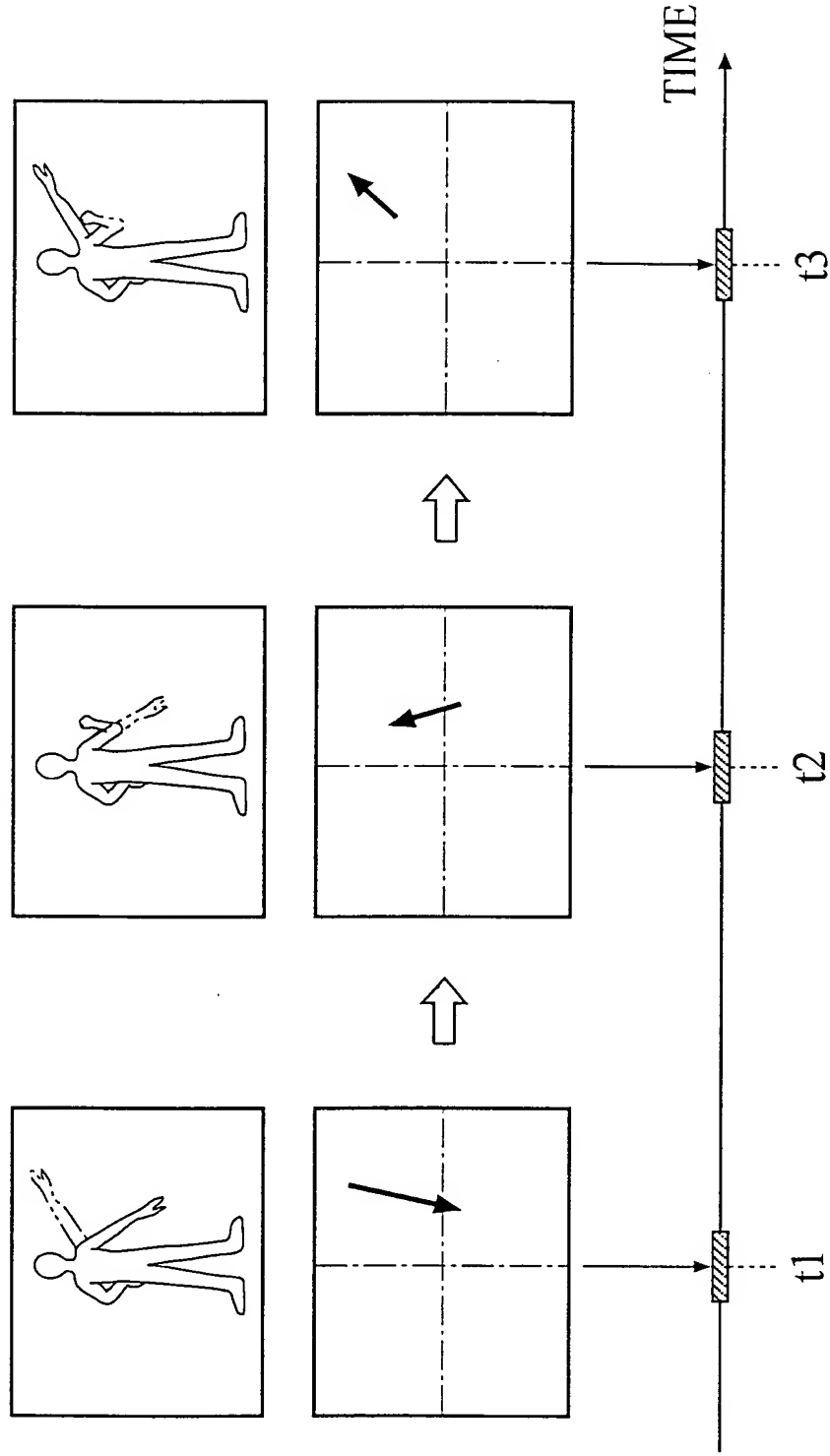


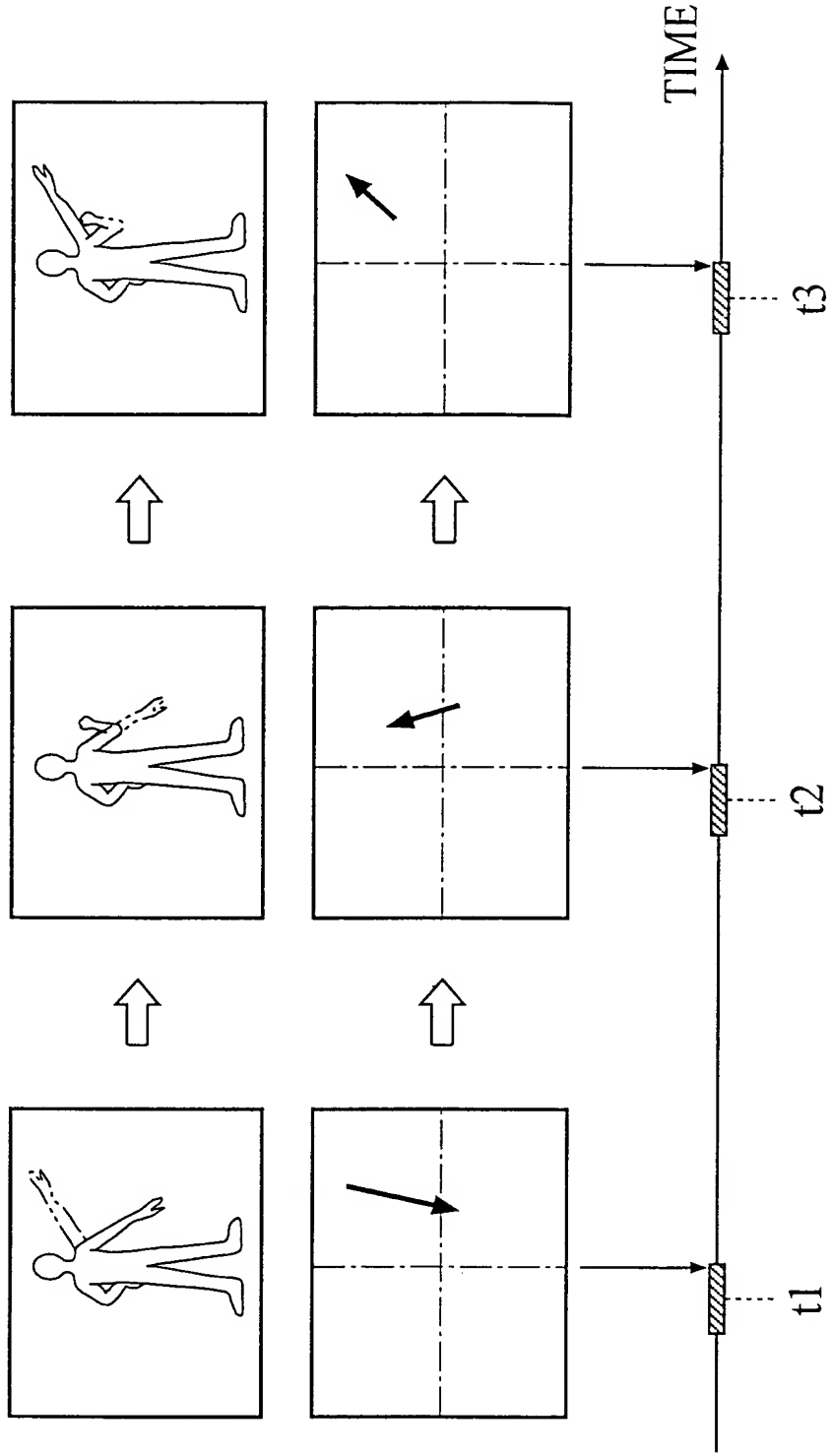
FIG.31B



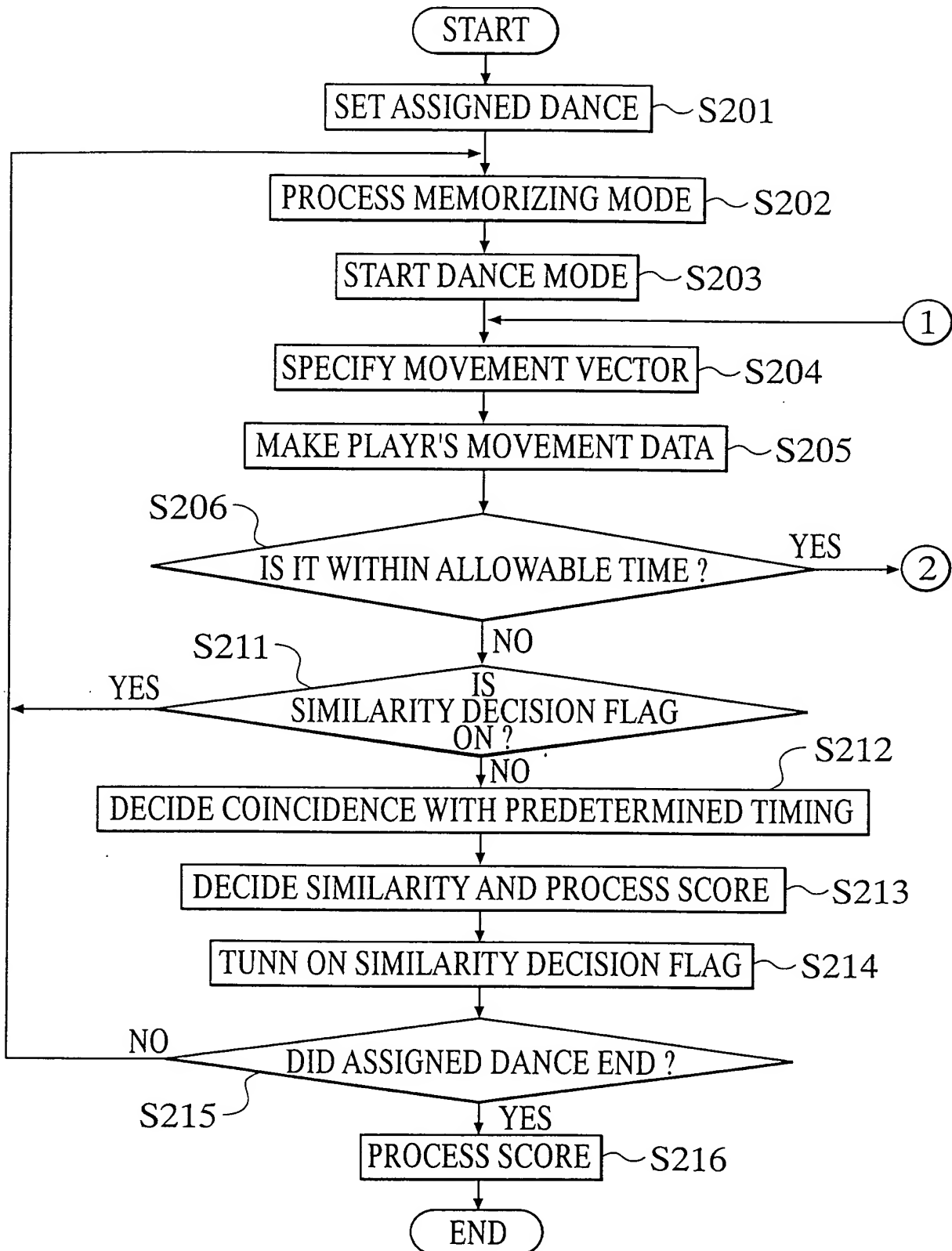
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FIG.32



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FIG.33



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FIG.34A



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FIG.34B

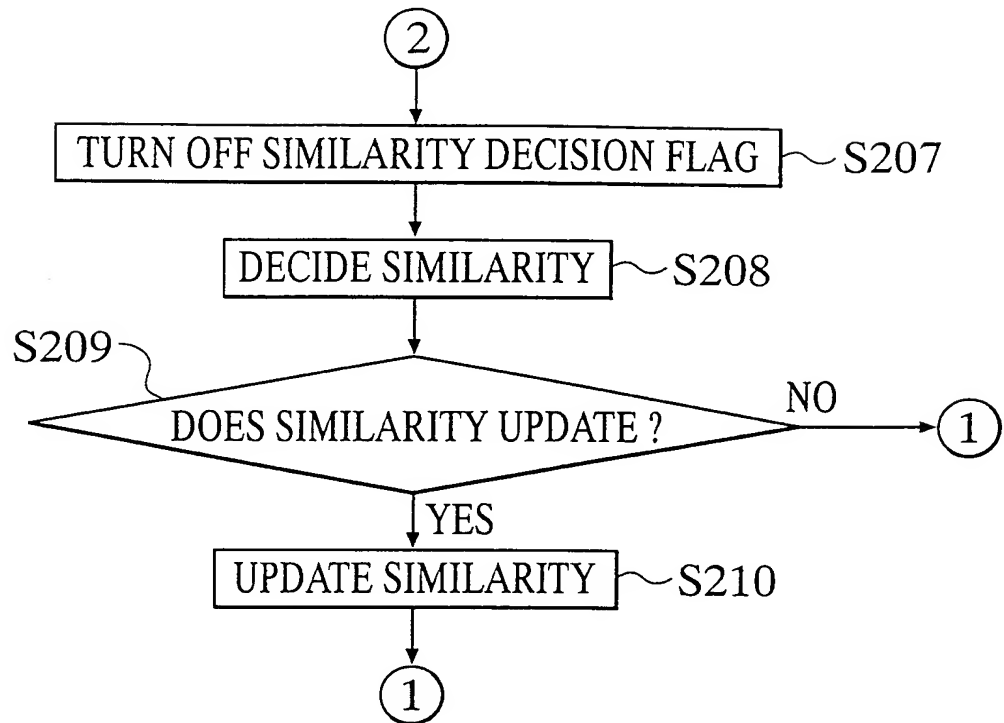
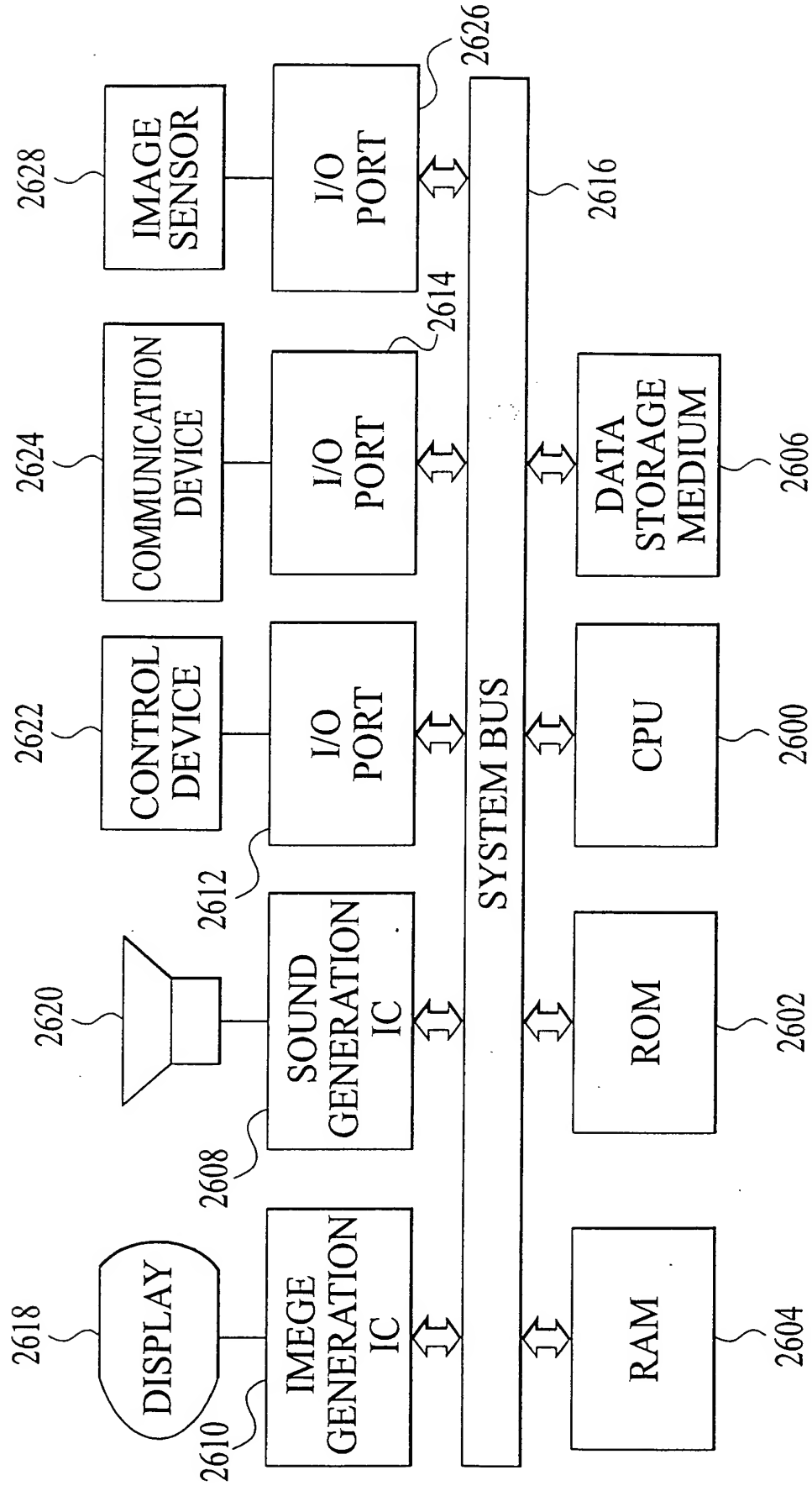


FIG.35



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FIG.36

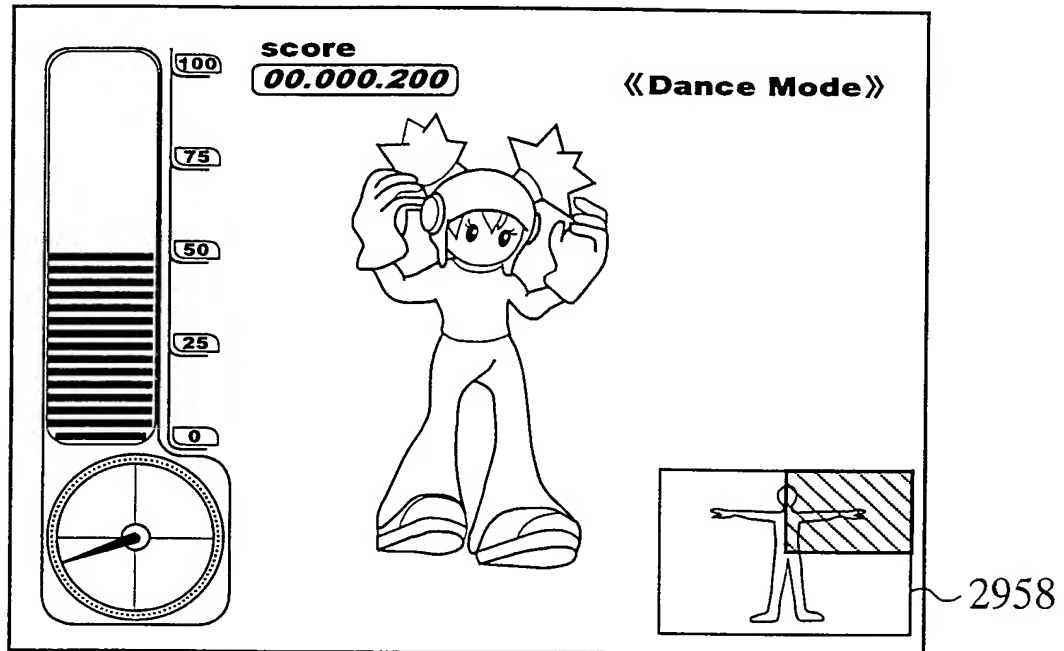


FIG.37

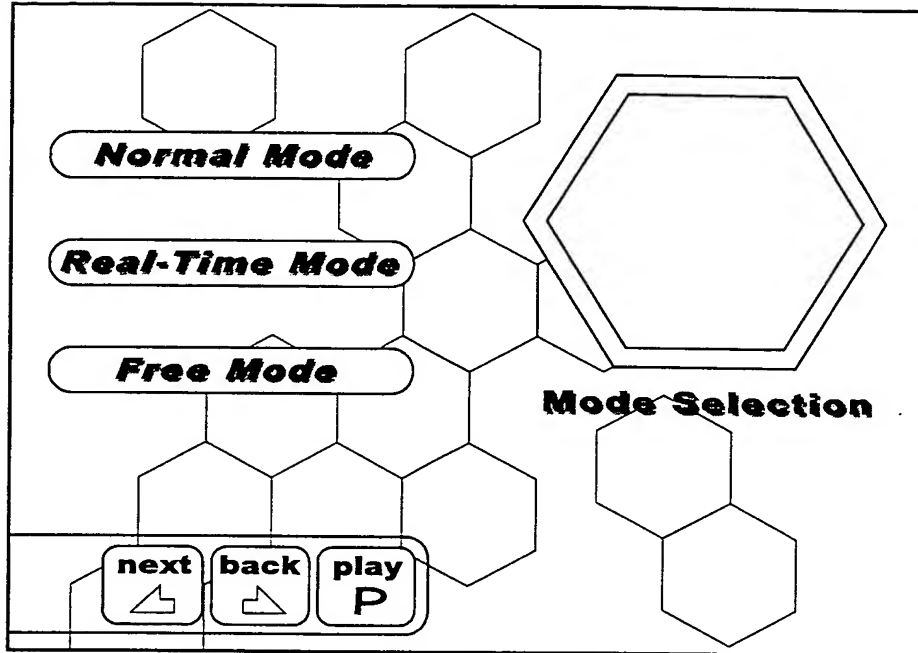


FIG.38

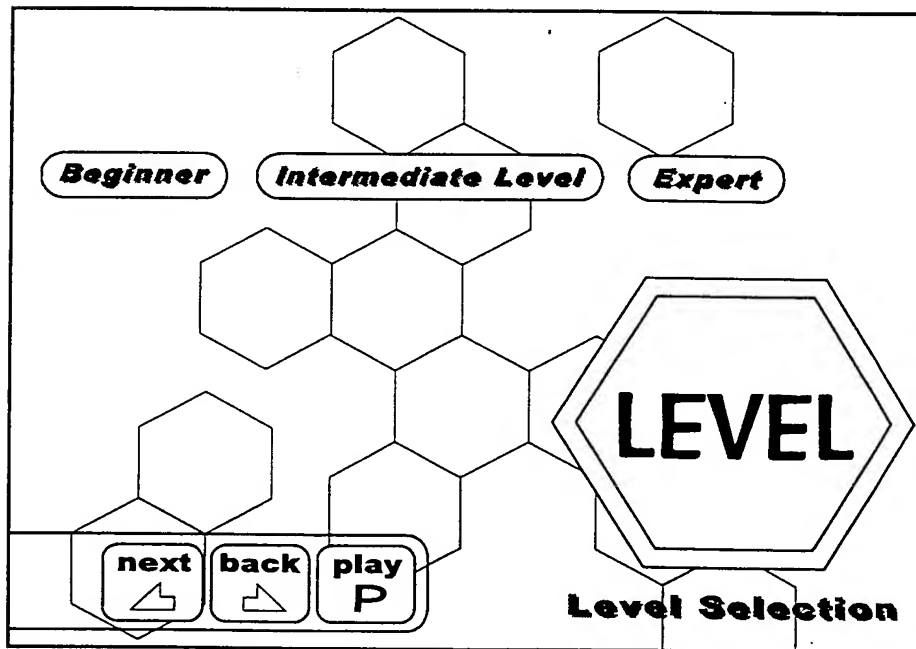


FIG.39

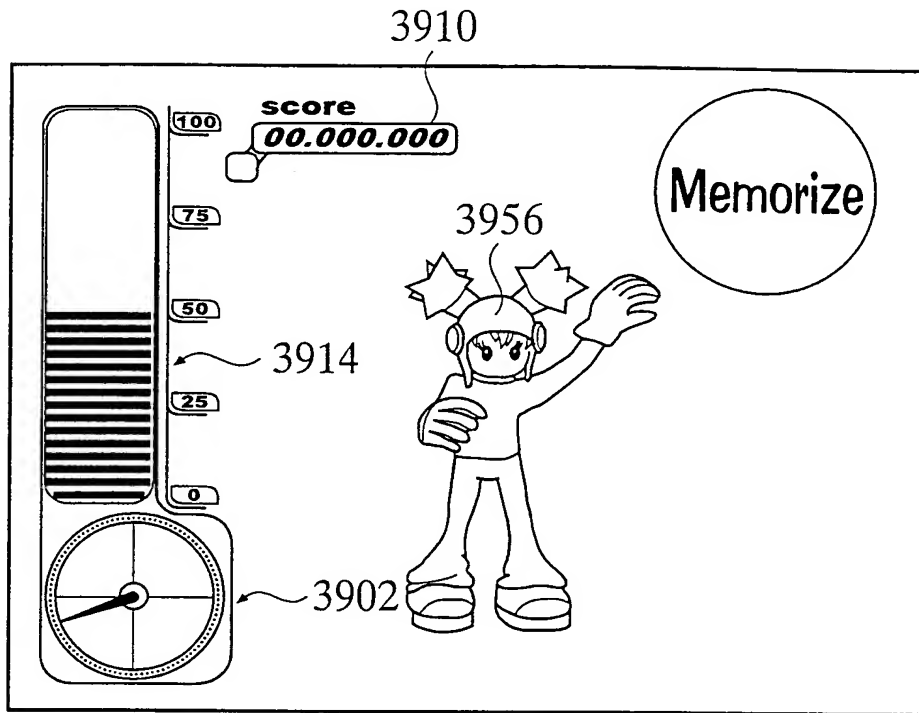
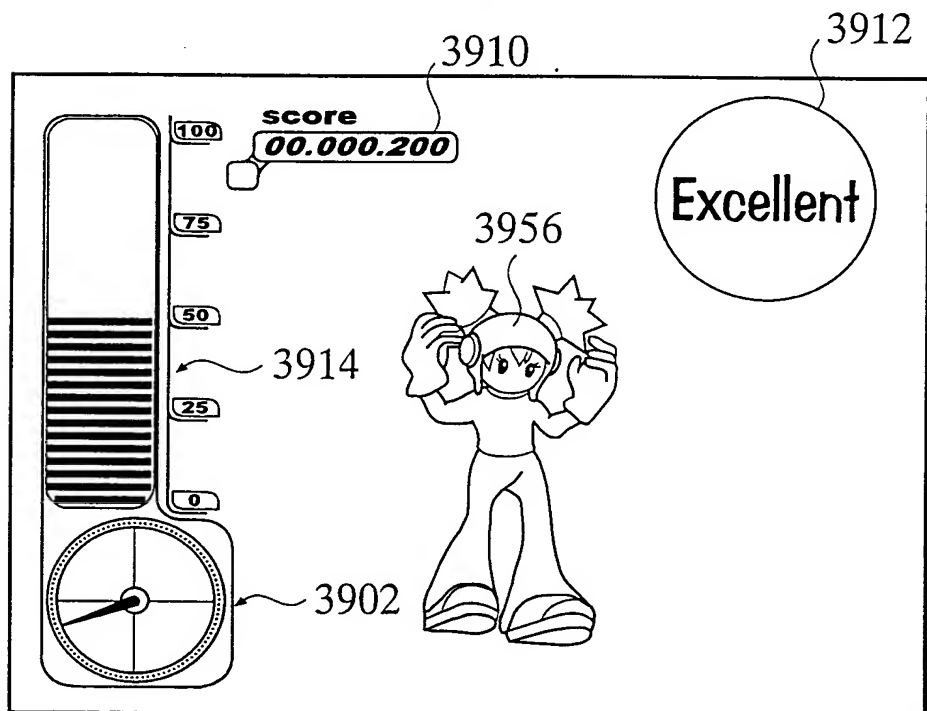


FIG.40



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FIG.41A

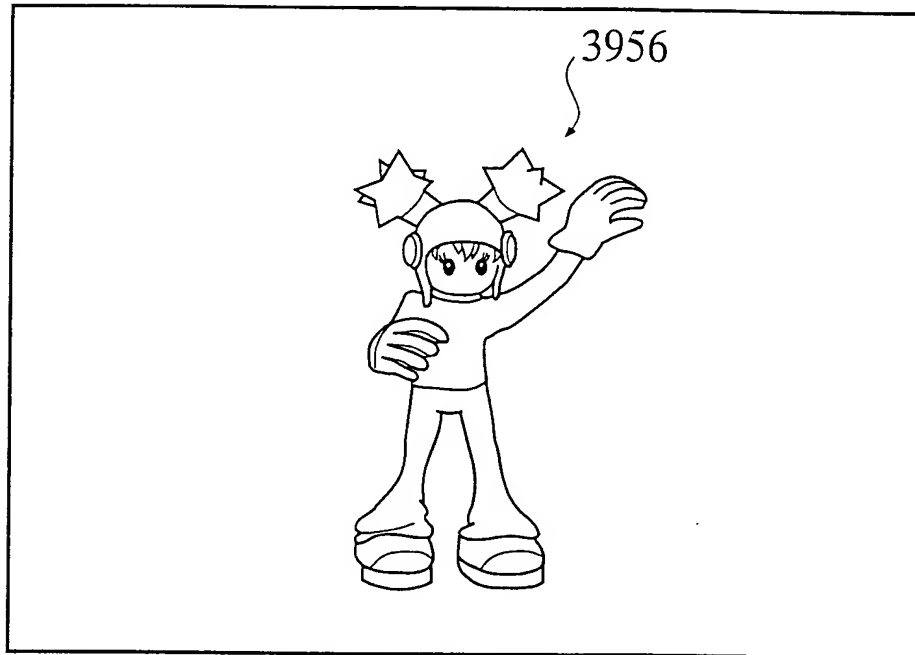


FIG.41B

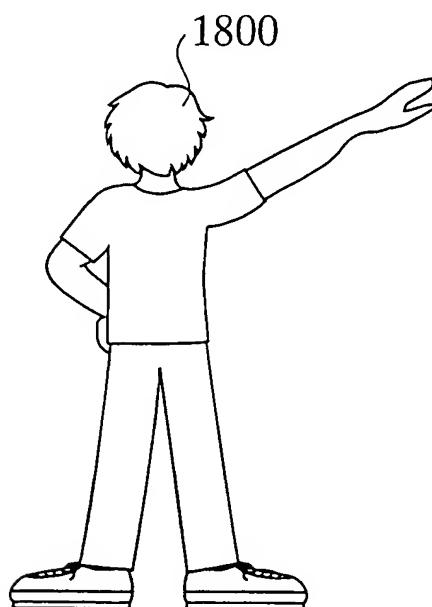
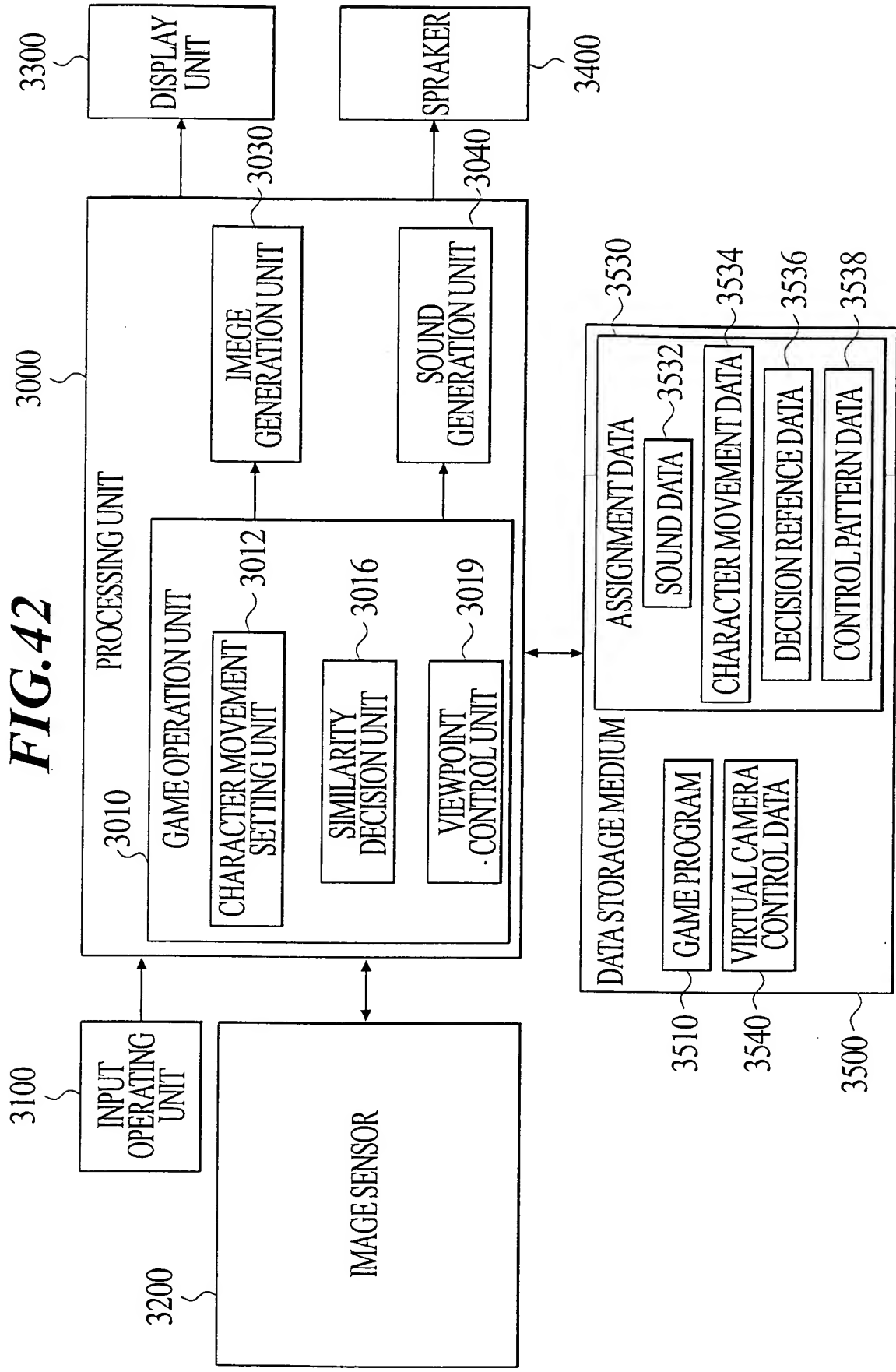


FIG. 42



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FIG.43

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MODE	LEVEL	BEFORE DANCE		DURING DANCE	
		CHARACTER CONTROL PATTERN	CAMERA CONTROL PATTERN	CHARACTER CONTROL PATTERN	CAMERA CONTROL PATTERN
NORMAL	BEGINNER	A	1	A	1
	INTERMEDIATE	A	1	A	2
	EXPERT	A	1	B	1
REAL-TIME	—	N/A	N/A	A	1
FREE	—	N/A	N/A	B	2

FIG.44

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(COORDINATES: X, Y, Z)

DANCE 1	POSITION DATA			
	FRAME 1	FRAME 2	FRAME 3	...
A	PART a	(Xa11, Ya11, Za11)	(Xa12, Ya12, Za12)	(Xa13, Ya13, Za13)
	PART b	(Xb11, Yb11, Zb11)	(Xb12, Yb12, Zb12)	(Xb13, Yb13, Zb13)
	PART c	(Xc11, Yc11, Zc11)	(Xc12, Yc12, Zc12)	(Xc13, Yc13, Zc13)
	⋮	⋮	⋮	...
B	PART a	(Xa21, Ya21, Za21)	(Xa22, Ya22, Za22)	(Xa23, Ya23, Za23)
	PART b	(Xb21, Yb21, Zb21)	(Xb22, Yb22, Zb22)	(Xb23, Yb23, Zb23)
	PART c	(Xc21, Yc21, Zc21)	(Xc22, Yc22, Zc22)	(Xc23, Yc23, Zc23)
	⋮	⋮	⋮	...

FIG.45A

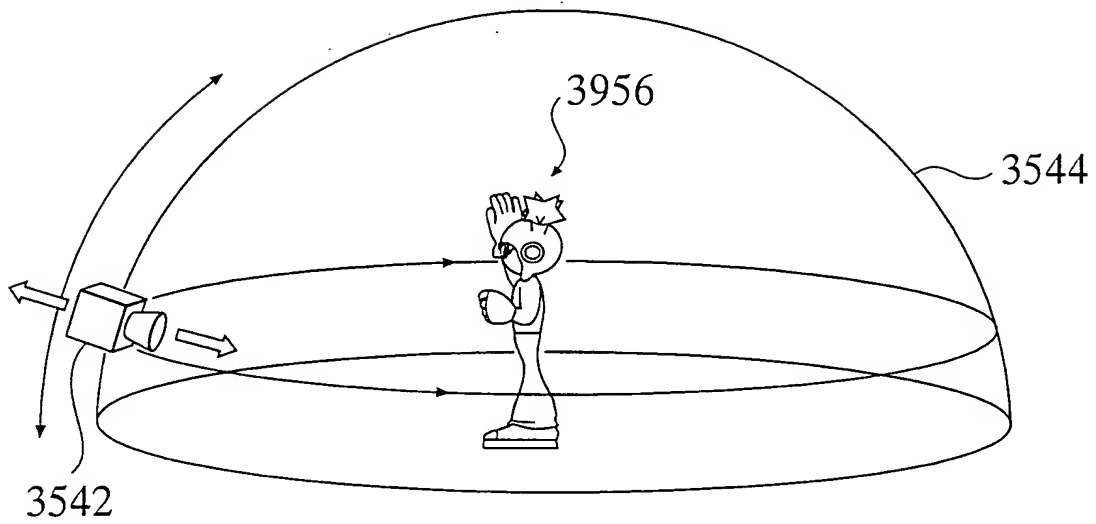


FIG.45B

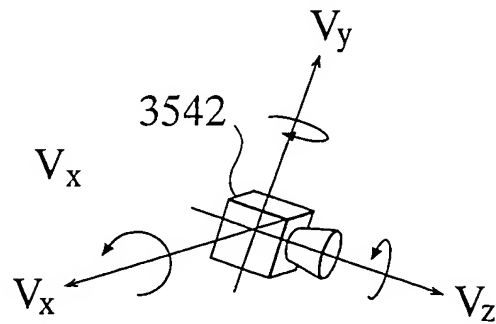


FIG.46

3540



SET VALUE	
CAMERA CONTROL PATTERN 1	POSITION (Vd11, Vi11, Vk11)
	DIRECTION (Vx11, Vy11, Vz11)
	ANGLE OF VIEW Z11
CAMERA CONTROL PATTERN 2	POSITION (Vd21, Vi21, Vk21)→(Vd22, Vi22, Vk22)→(Vd23, Vi23, Vk23)→(Vd24, Vi24, Vk24)
	DIRECTION (Vx21, Vy21, Vz21)
	ANGLE OF VIEW Z21

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FIG.47

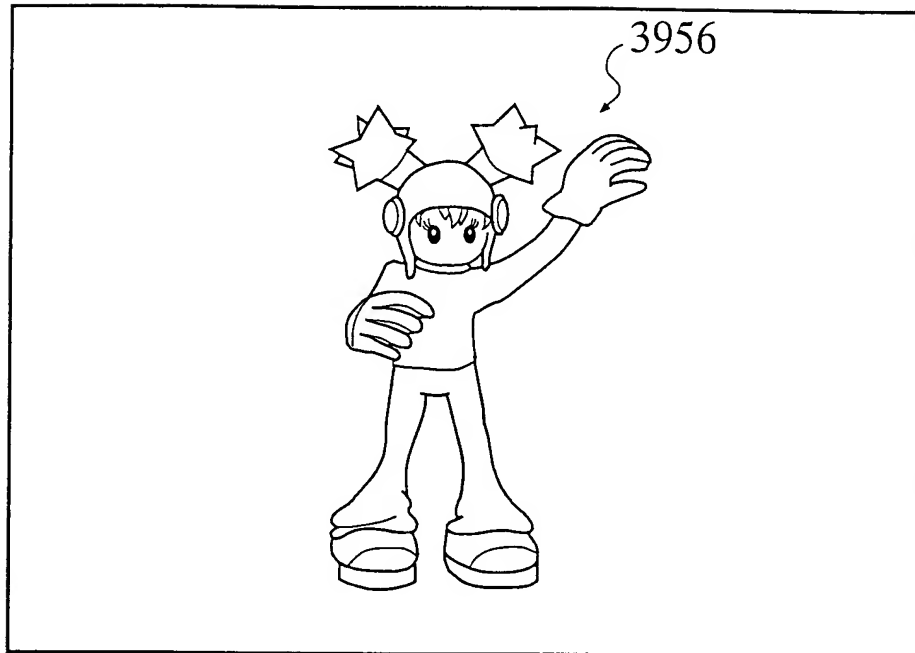
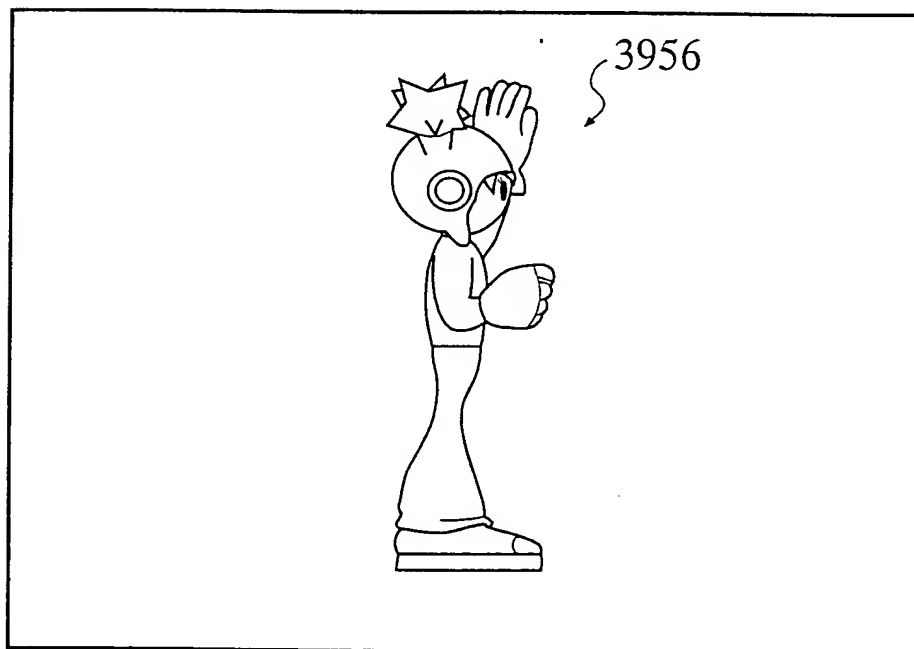


FIG48



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FIG.49

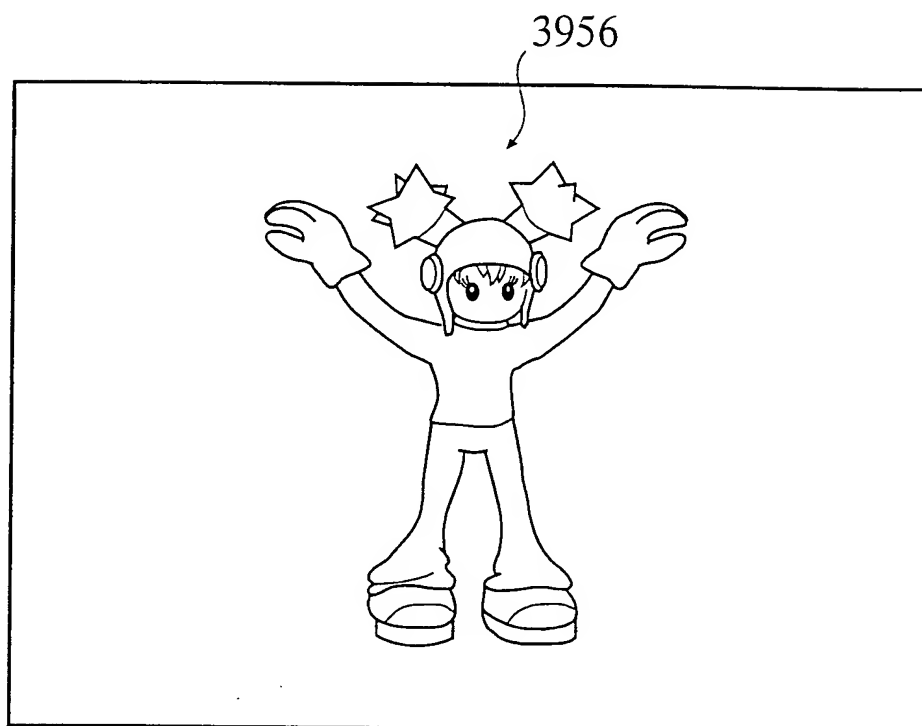


FIG.50

3536



(DIRECTION α , MAGNITUDE β , SPEED γ)

DECISION REFERENCE DATA			
	t1	t2	t3
DANCE 1	$(\alpha\ 11, \beta\ 11, \gamma\ 11)$	$(\alpha\ 12, \beta\ 12, \gamma\ 12)$	$(\alpha\ 13, \beta\ 13, \gamma\ 13)$
DANCE 2	$(\alpha\ 11', \beta\ 11', \gamma\ 11')$	$(\alpha\ 12', \beta\ 12', \gamma\ 12')$	$(\alpha\ 13', \beta\ 13', \gamma\ 13')$
			...

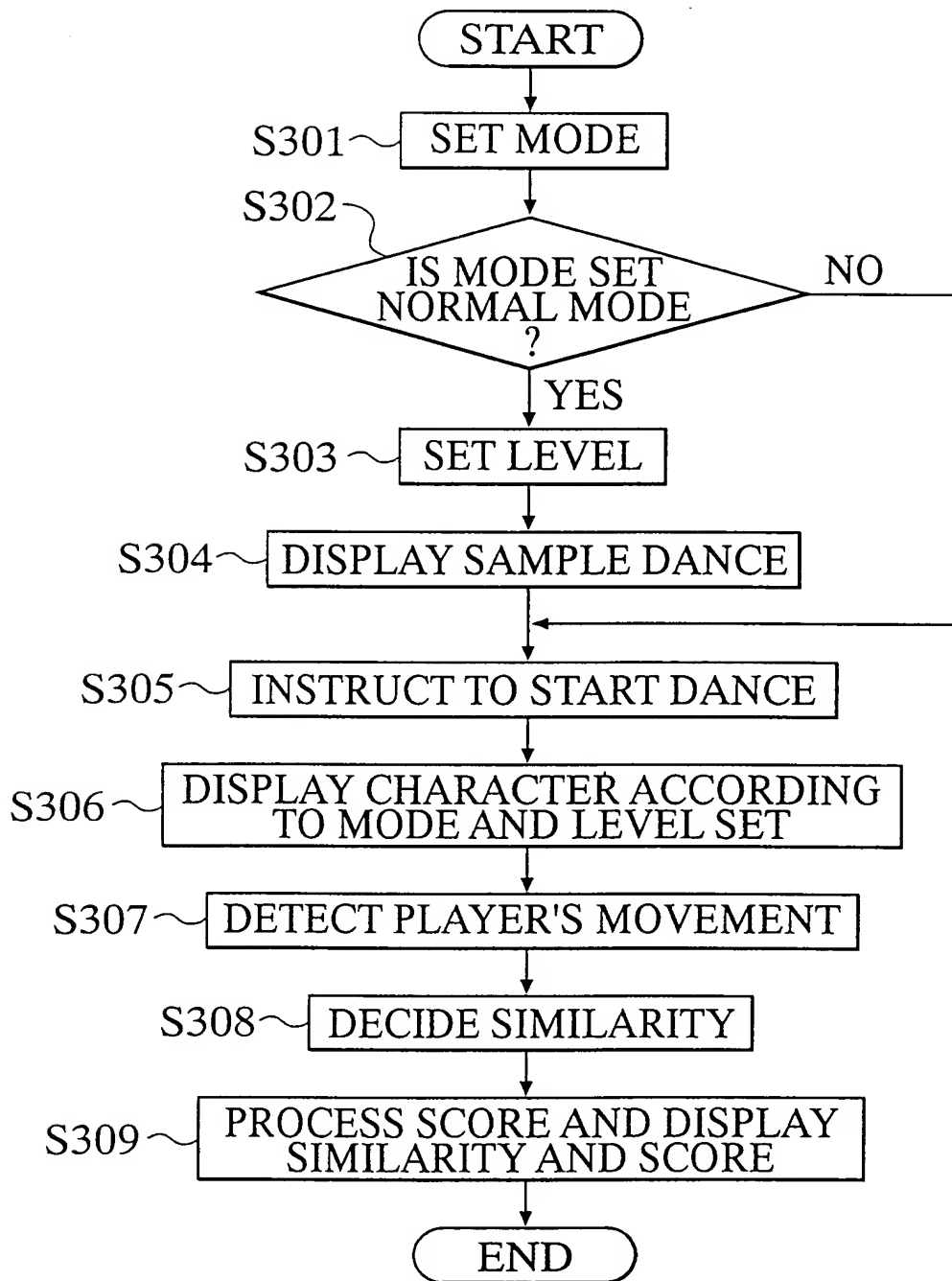
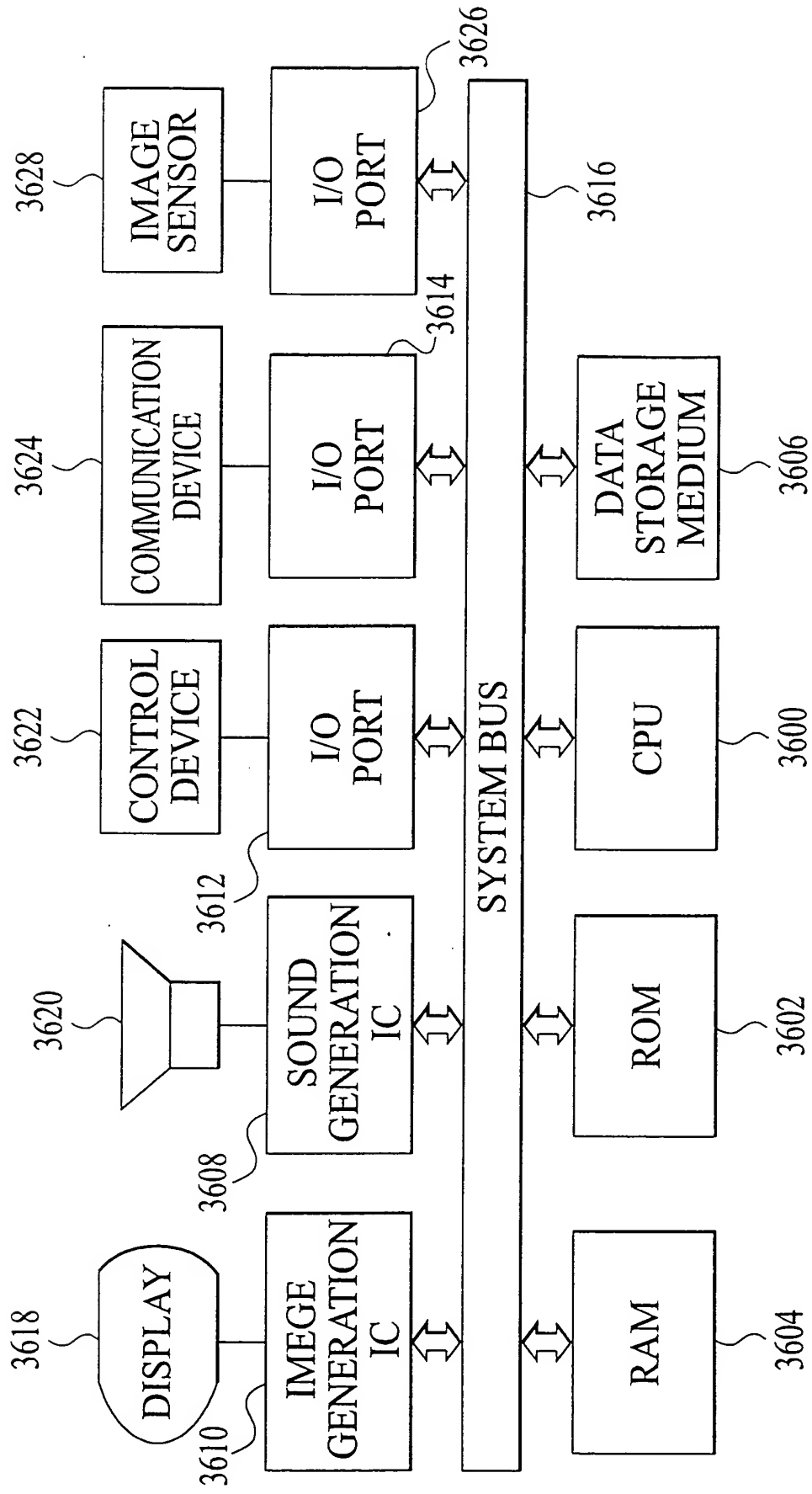
FIG.51

FIG. 52



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FIG.53

